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Baurer et al.

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(54) **SEEDING CONTROL SYSTEM AND METHOD**

(58) **Field of Classification Search**
None
See application file for complete search history.

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(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 280 days.

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Primary Examiner — Todd M Melton
Assistant Examiner — Jason R Roberson

Related U.S. Application Data

(57) **ABSTRACT**

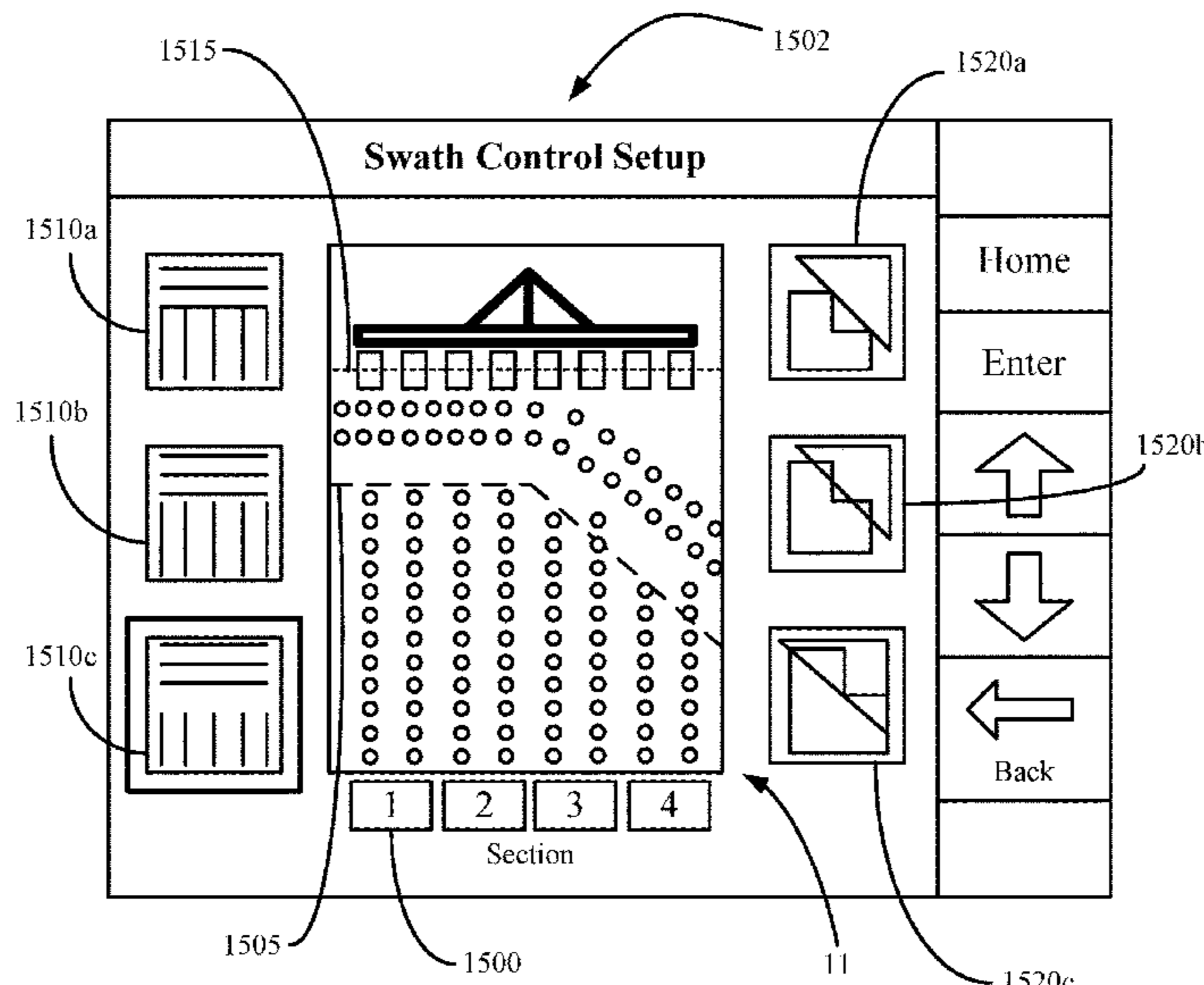
(63) Continuation of application No. 13/812,483, filed as application No. PCT/US2011/045587 on Jul. 27, 2011, now Pat. No. 9,955,625.
(Continued)

A seeding control system and method to improve yield by minimizing overplanting and underplanting during planting operations. As the planter traverses the field, a precise seed placement map is created by associating the time of each seed pulse generated by the seed sensors with the location of a GPS unit. Based on the generated seed placement map, a stop-planting boundary is defined by previously planted seed or other field boundary such that when a swath of the planter crosses over the stop-planting boundary the swath controllers disengage the drivers of the corresponding seed meters to prevent planting of seeds. The swath controllers cause the drivers to reengage allowing planting to resume when the affected swaths pass out of the stop planting boundary.

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A01C 7/10 (2006.01)
G01C 21/00 (2006.01)
(Continued)

(52) **U.S. Cl.**
CPC *A01C 7/102* (2013.01); *A01C 7/107* (2013.01); *A01C 21/005* (2013.01); *G01C 21/00* (2013.01);
(Continued)

7 Claims, 32 Drawing Sheets



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H04L 5/00 (2006.01)
A01C 21/00 (2006.01)
- (52) **U.S. Cl.**
 CPC *H04L 5/001* (2013.01); *H04L 5/005* (2013.01); *H04L 5/0016* (2013.01); *H04L 5/0019* (2013.01); *H04L 5/0048* (2013.01); *H04L 5/0053* (2013.01); *A01C 7/105* (2013.01)

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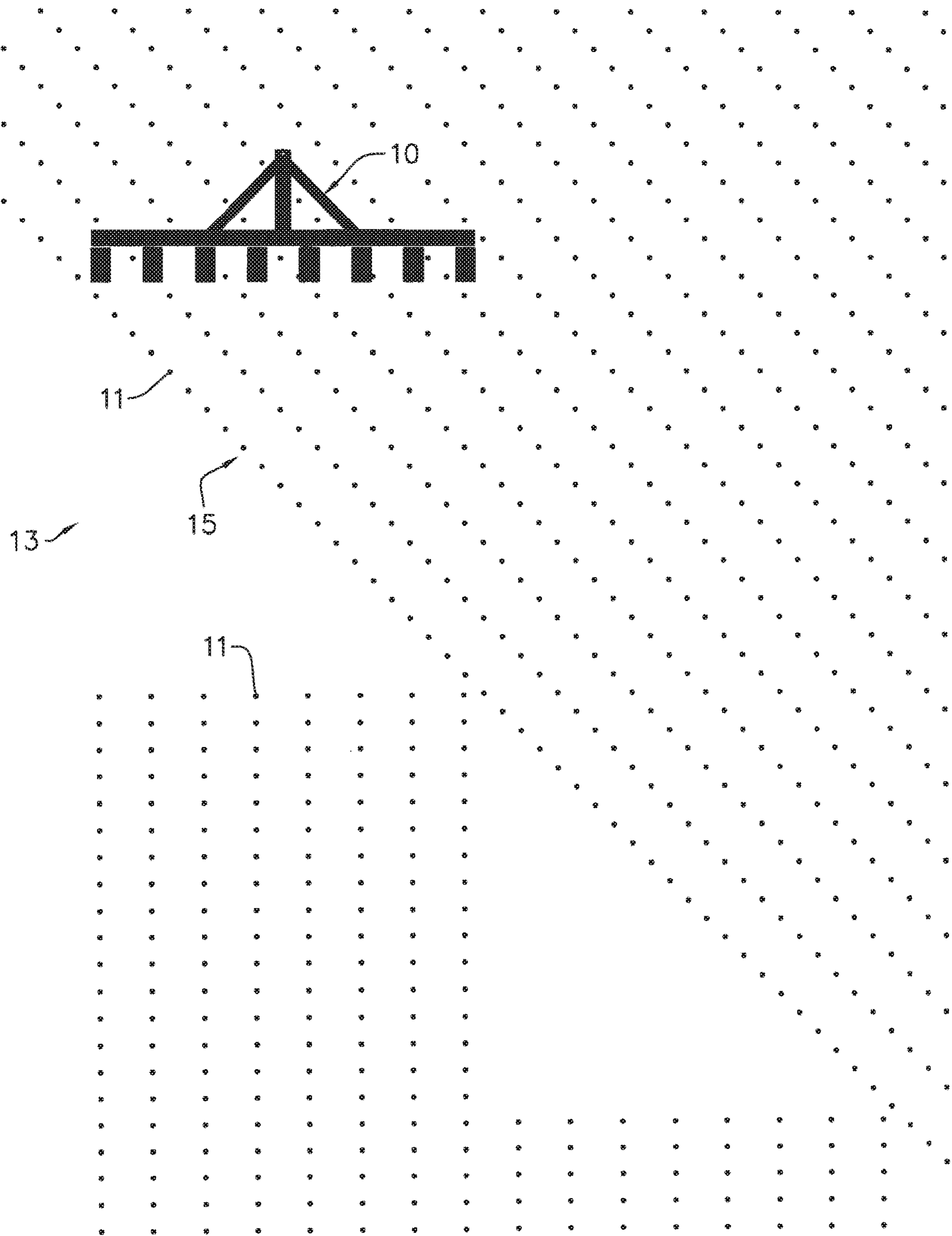


FIG. 1
(Planter w/o Swath Control - Underplant)

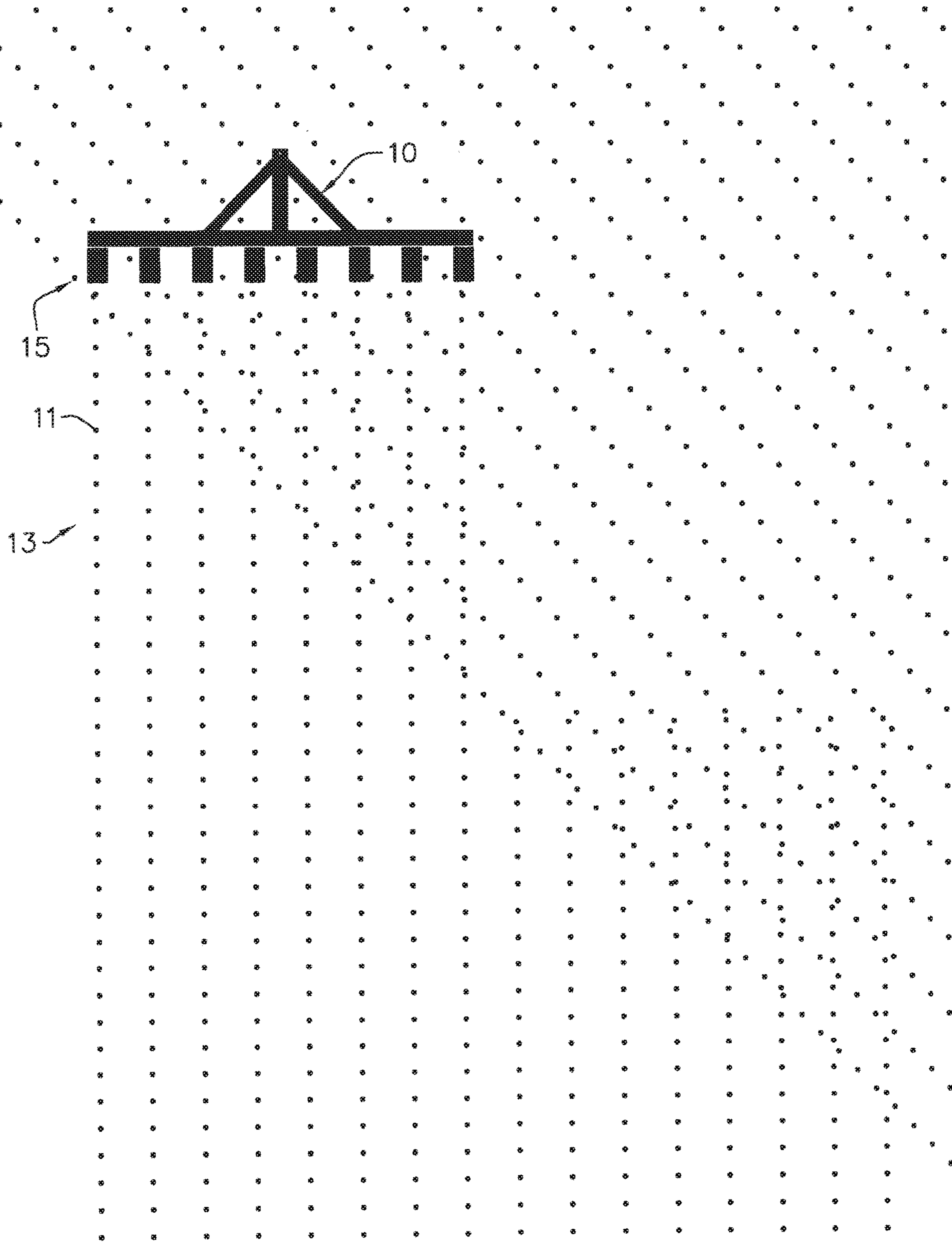


FIG. 2
(Planter w/o Swath Control – Overplant)

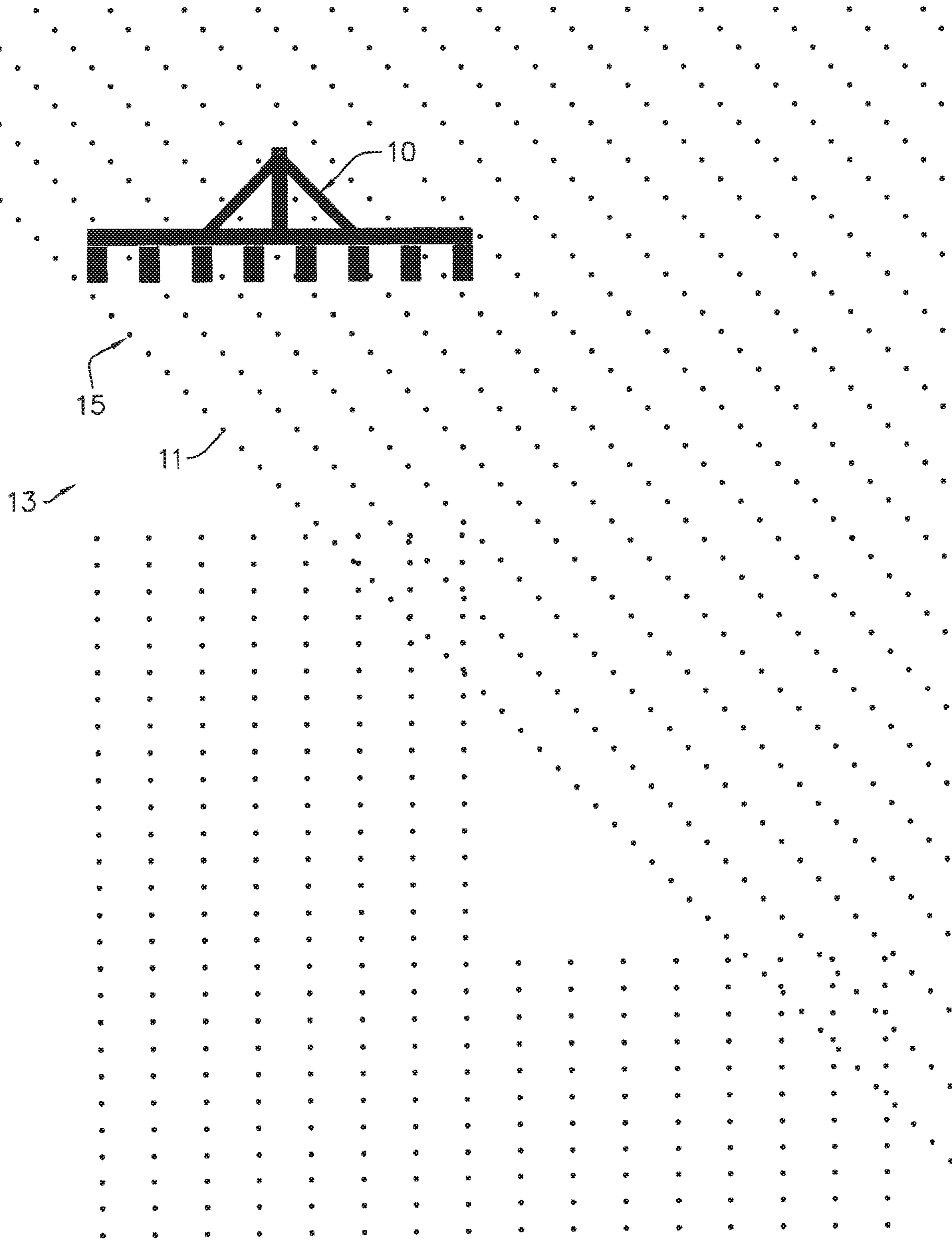


FIG. 3
(Planter w/o Swath Control - 50/50)

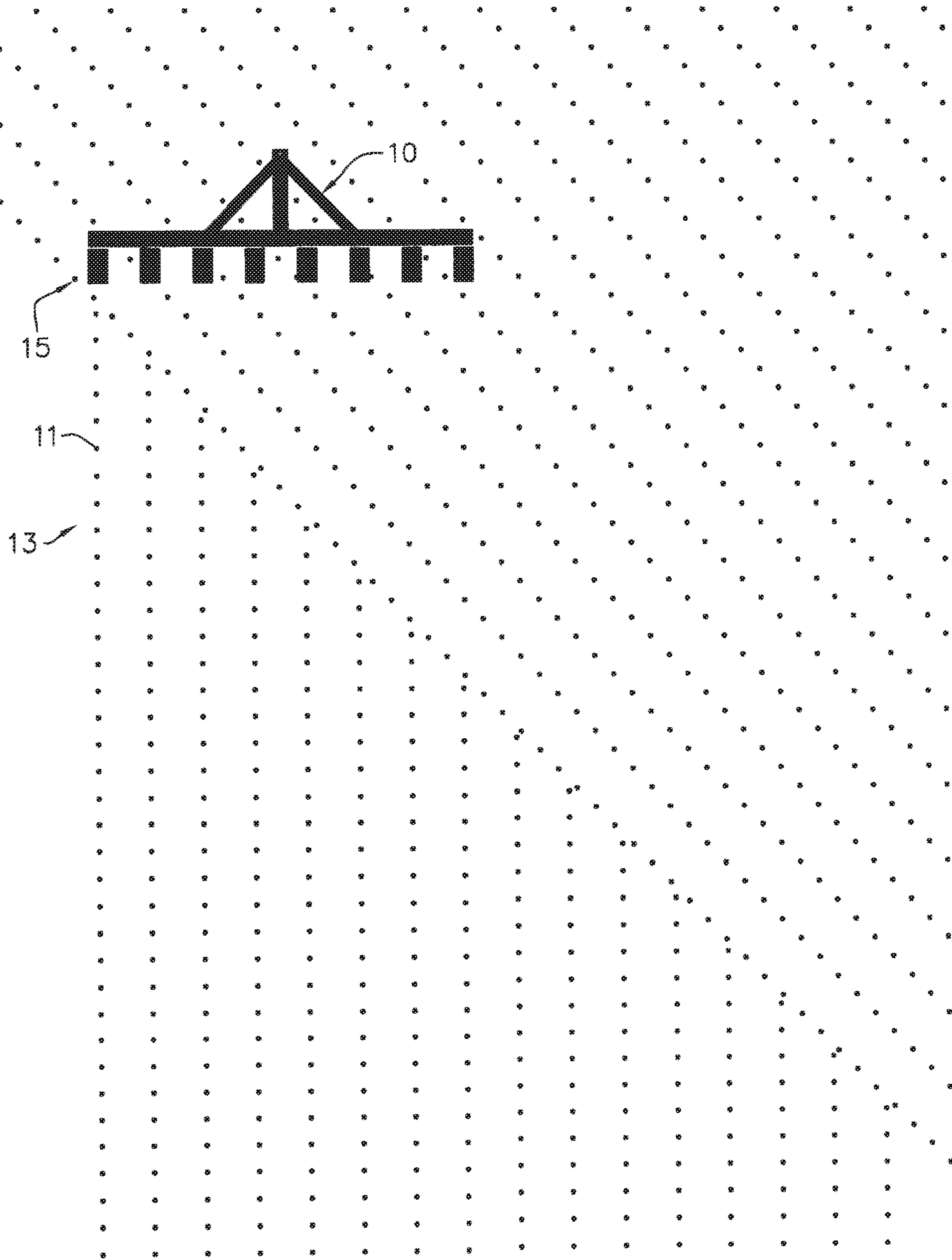


FIG. 4
(Planter w/ 1-Row Swath Control)

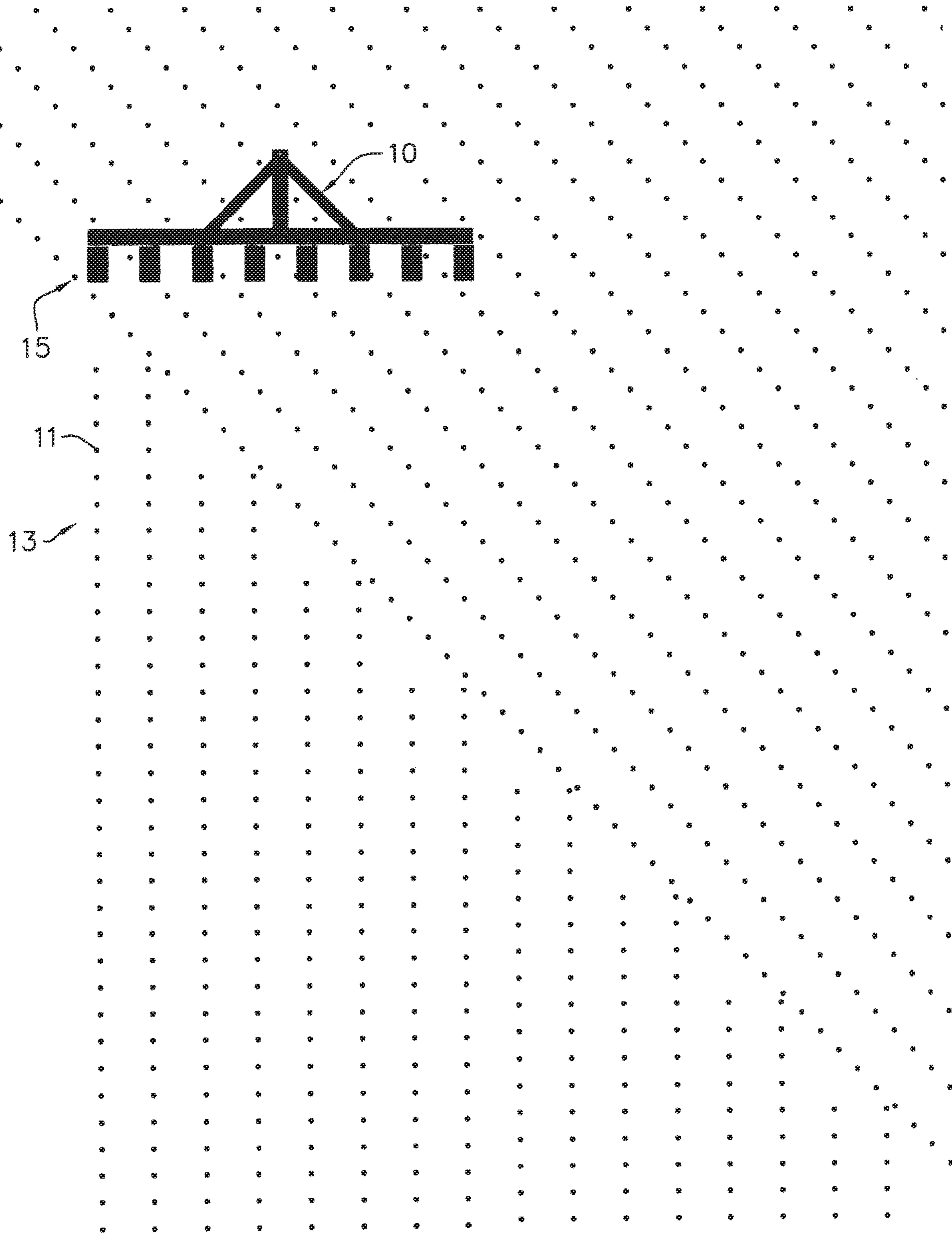


FIG. 5A
(Planter w/ 2-Row Swath Control - Underplant)

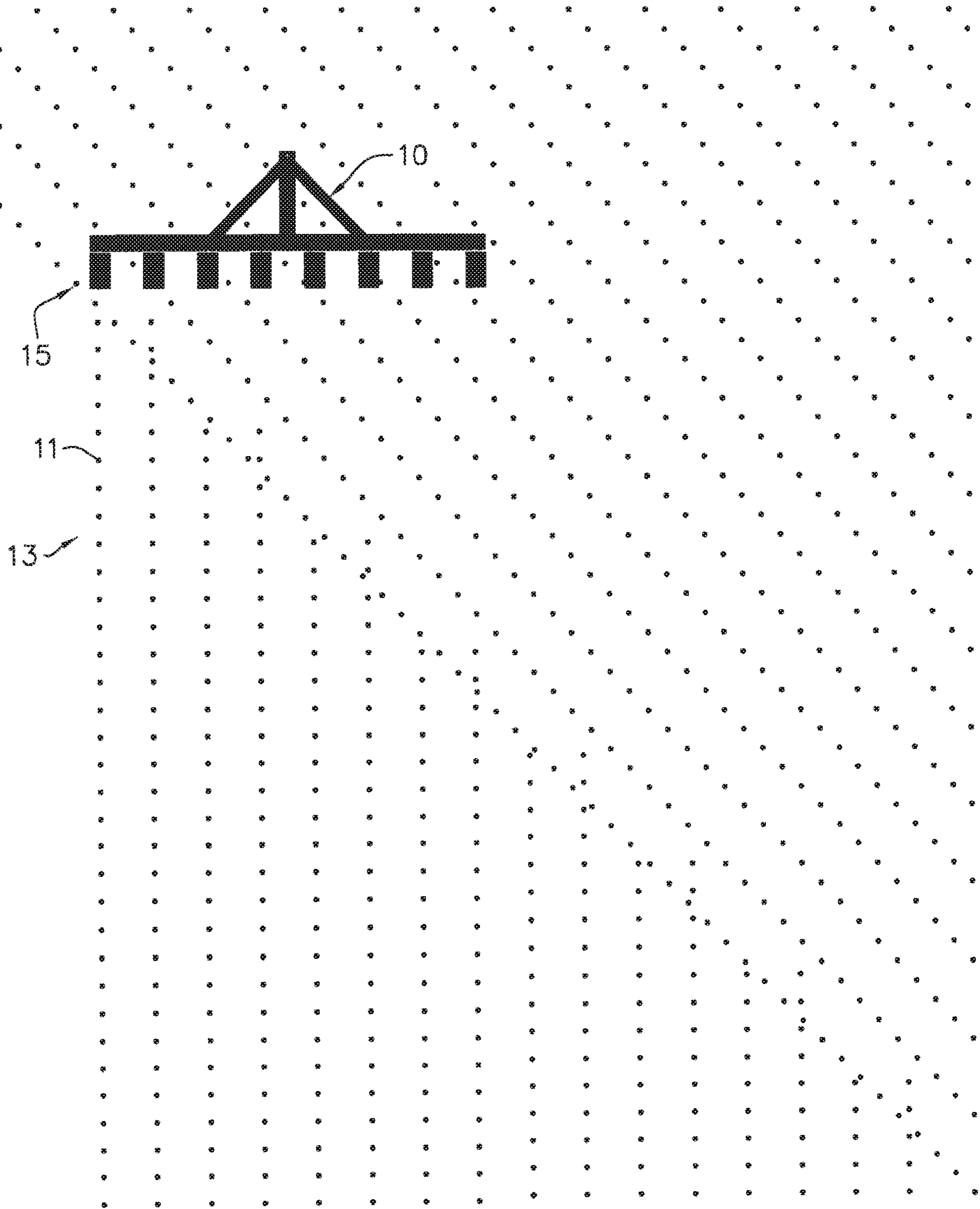


FIG. 5B
(Planter w/ 2-Row Swath Control - Overplant)

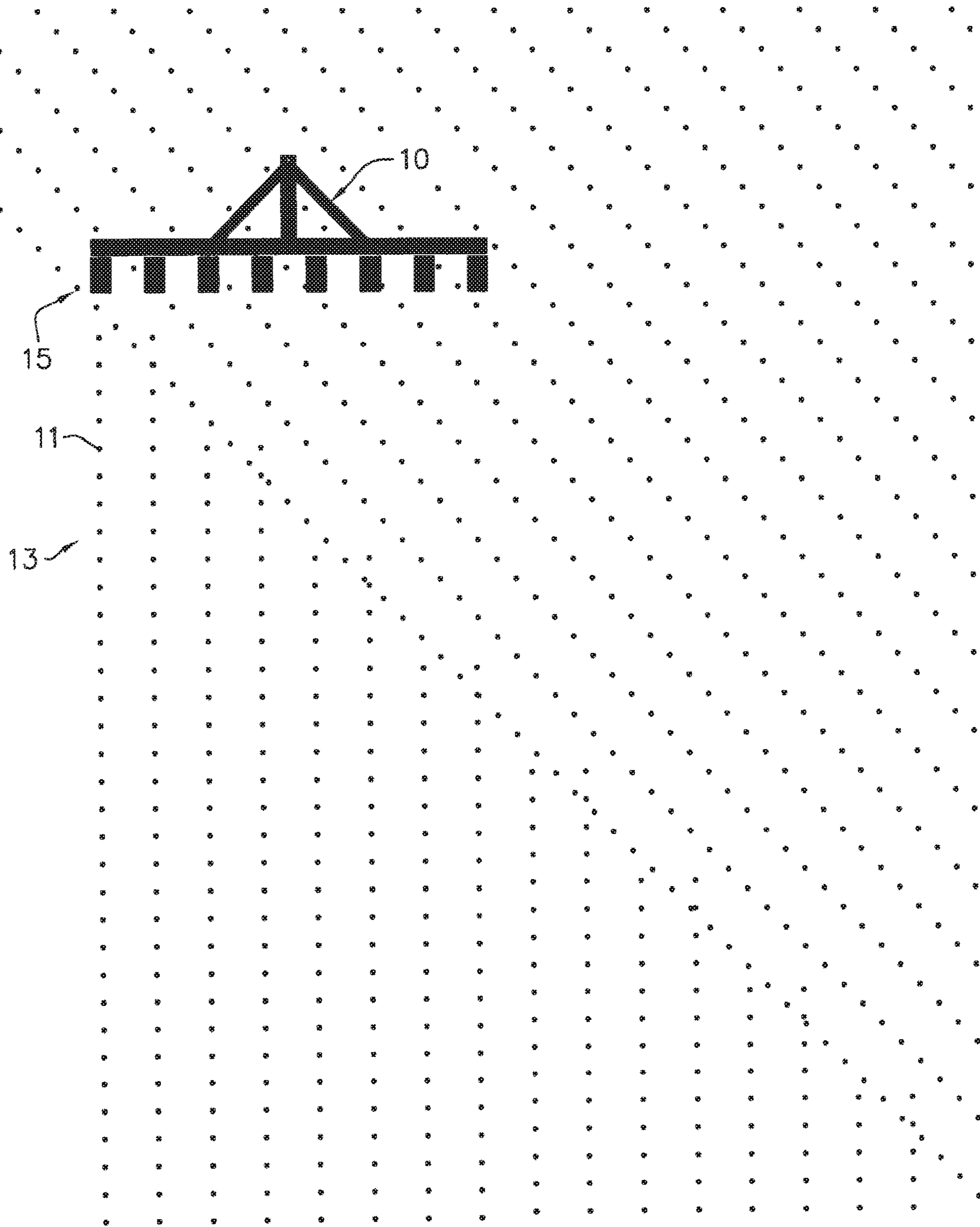


FIG. 5C
(Planter w/ 2-Row Swath Control - 50/50)

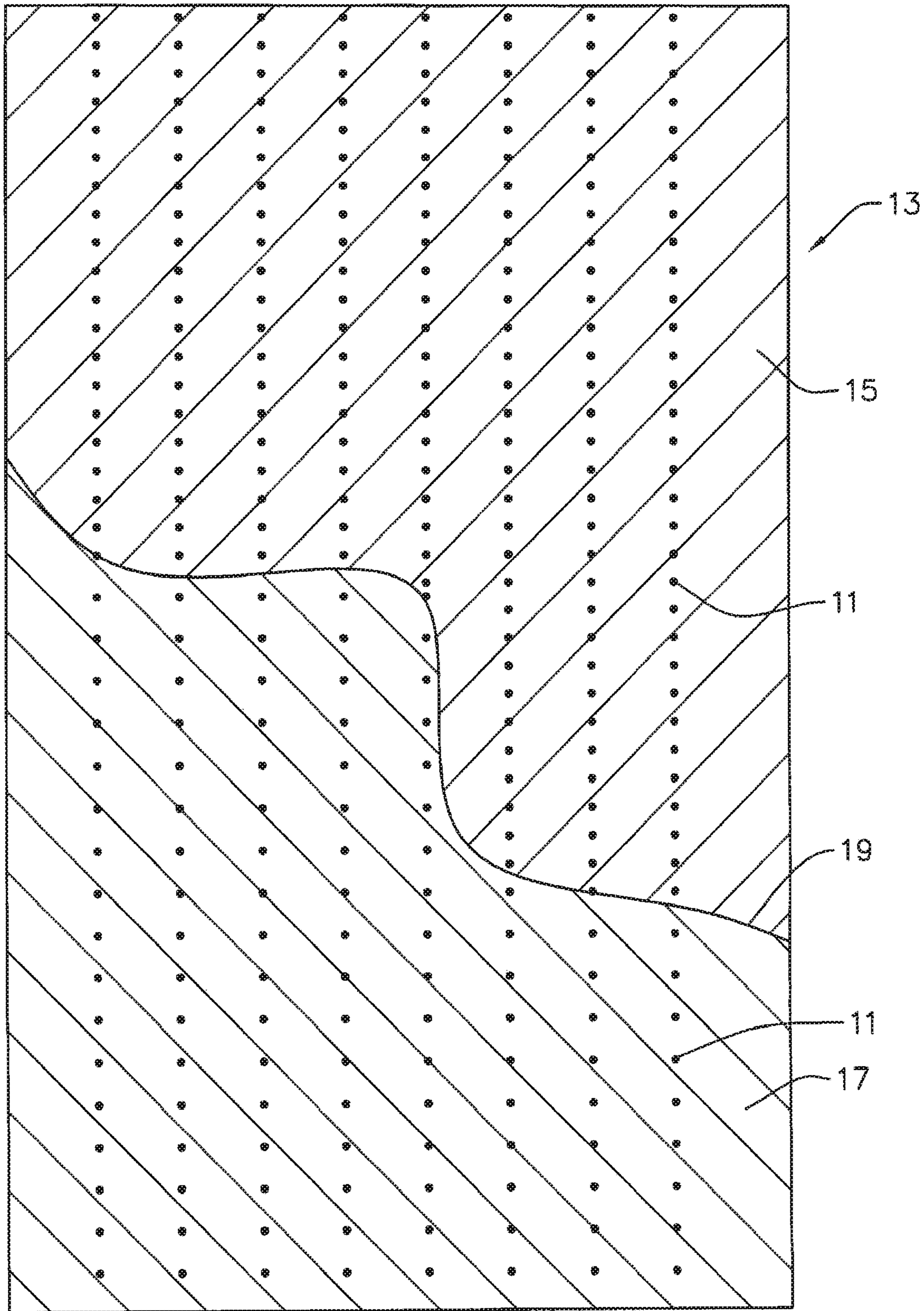


FIG. 6

(Planter w/ VRS and 1-Row Swath Control)

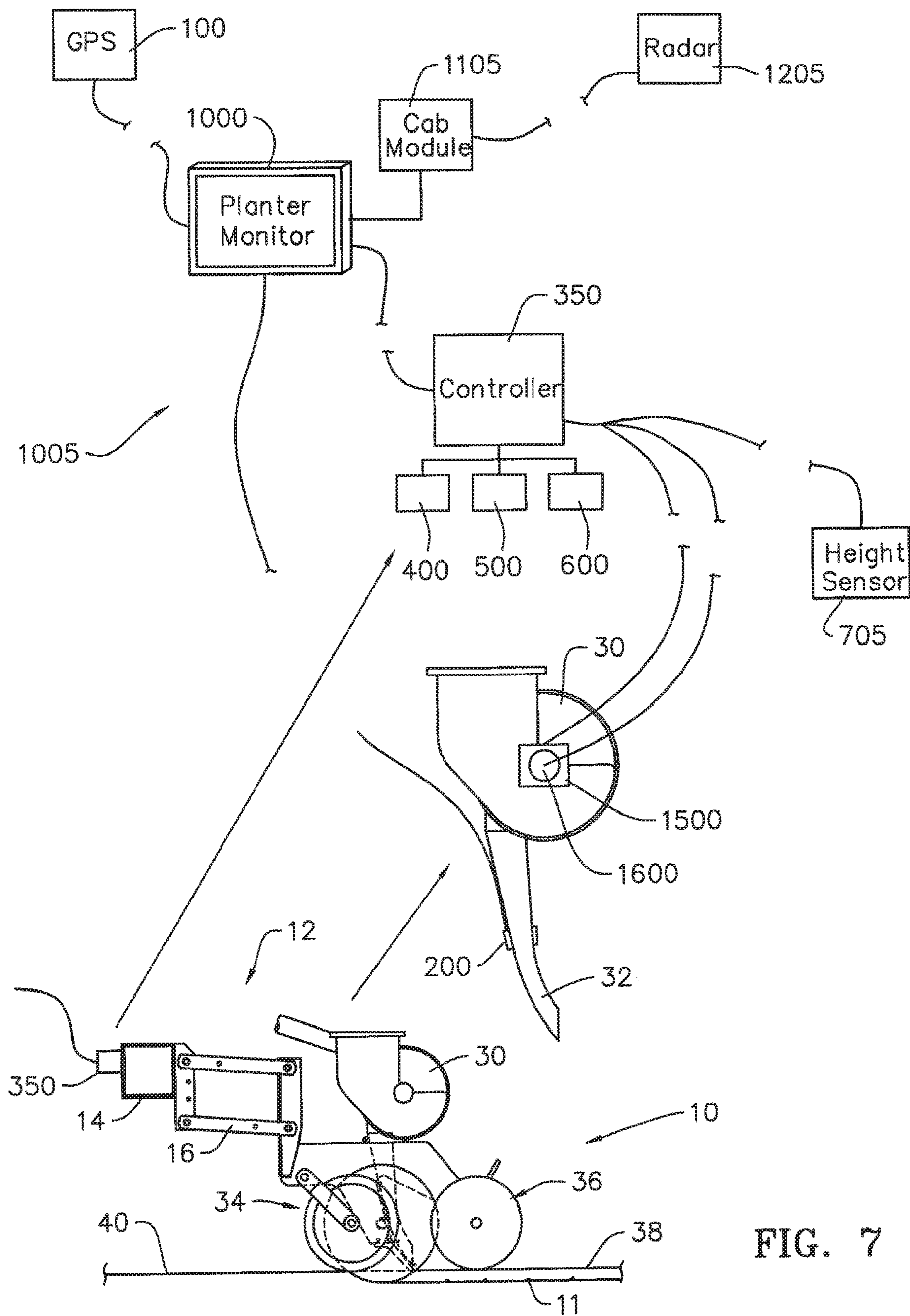


FIG. 7

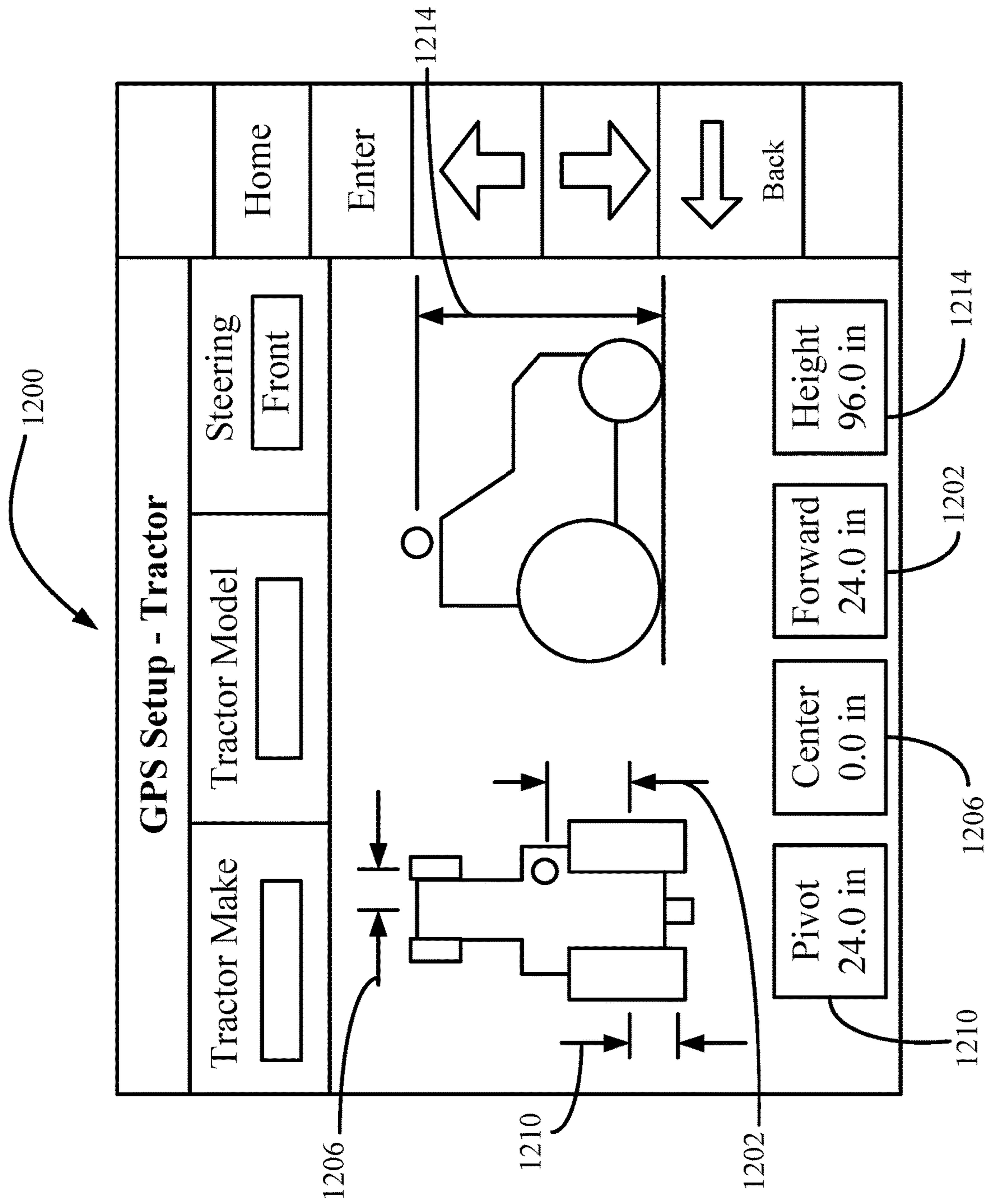


FIG. 8

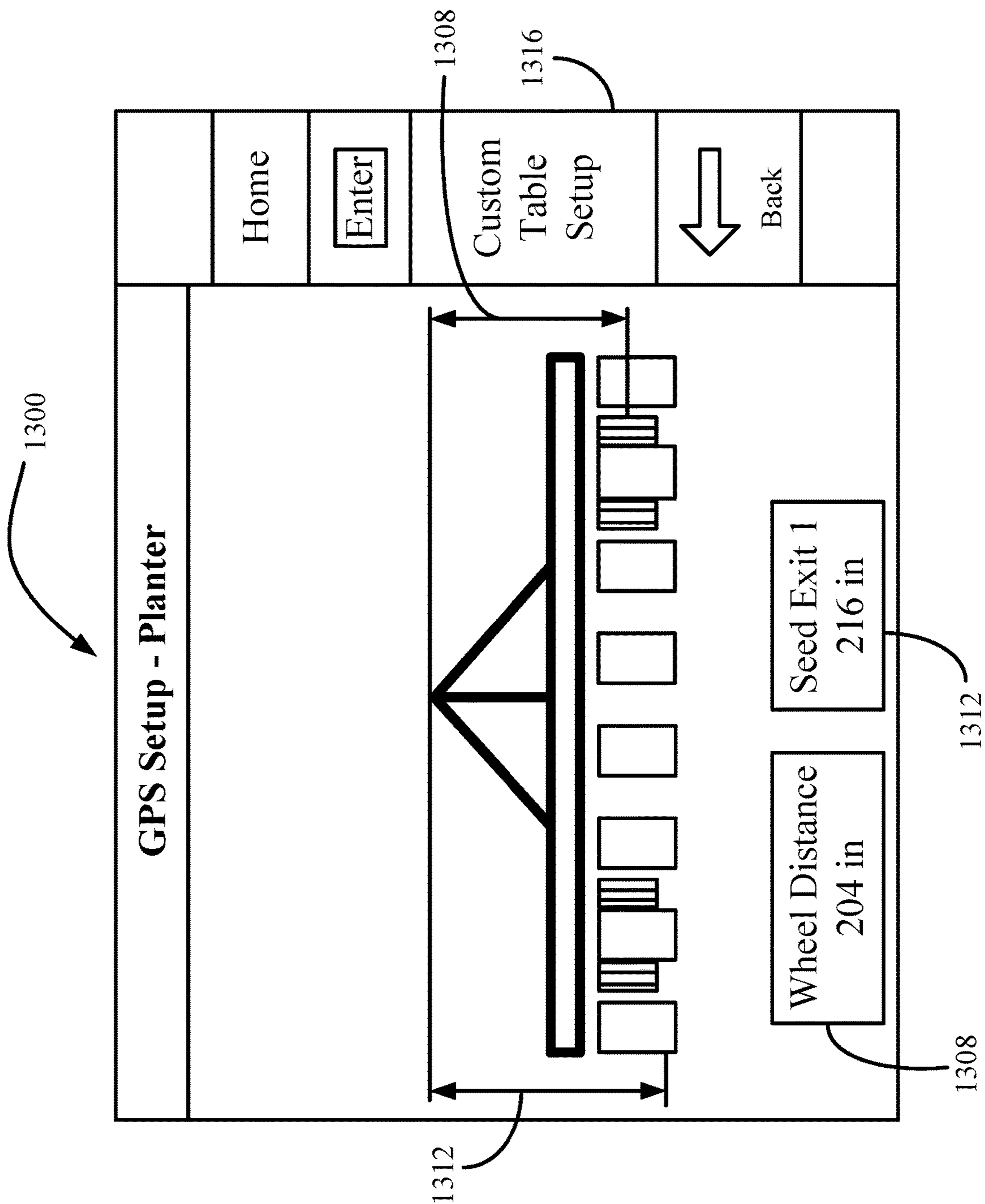


FIG. 9

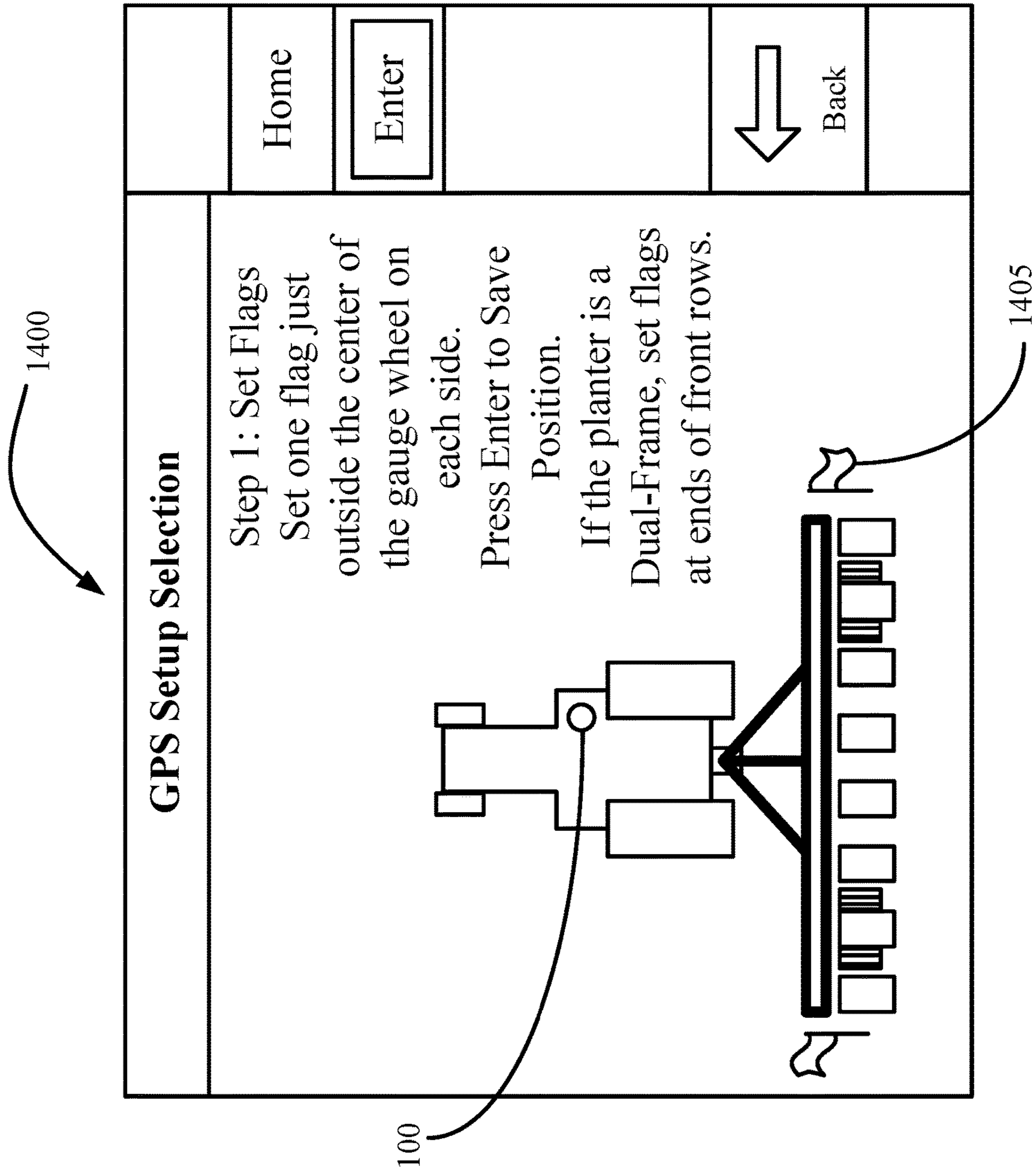
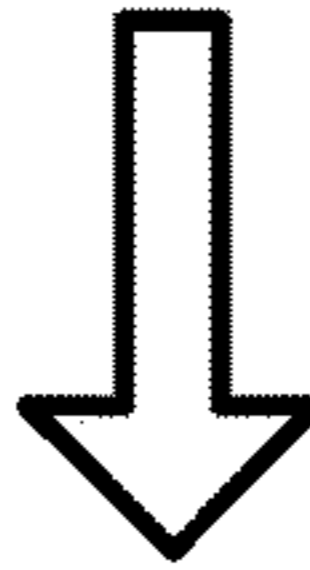
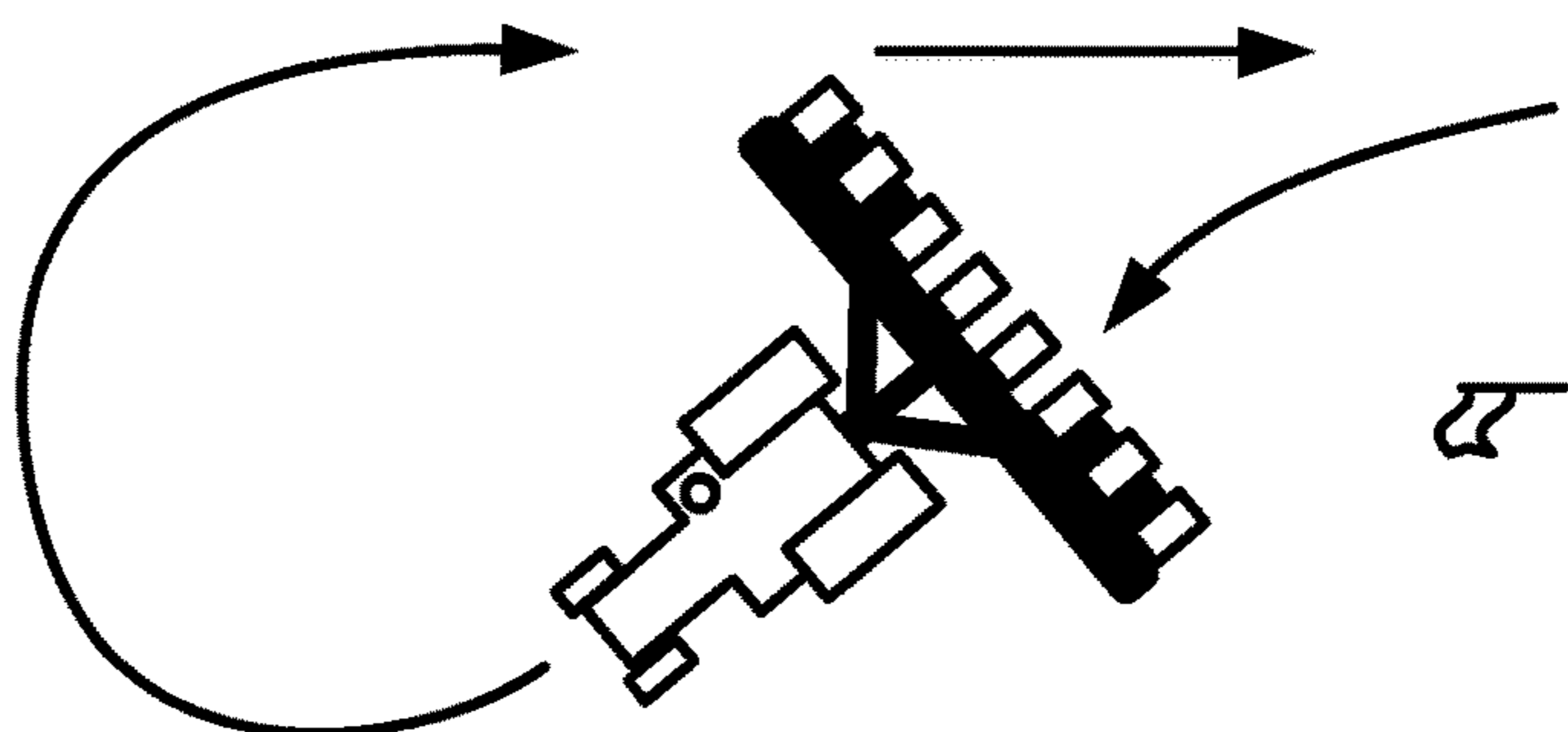


FIG. 10A

1410

GPS Setup Selection	
	Home
	Enter
	 Back

Step 2: Turn Around
Drive forward and turn around and drive toward the flags, making sure the approach is directly into the flags. Press Enter to Continue when front of tractor is between the flags.



The diagram shows a tractor with a series of flags on its front. A curved arrow indicates the tractor turning around. A straight arrow points forward from the tractor towards a set of flags. A curved arrow points from the tractor back towards the flags, indicating a return path. The flags are represented by a series of vertical bars.

FIG. 10B

1420

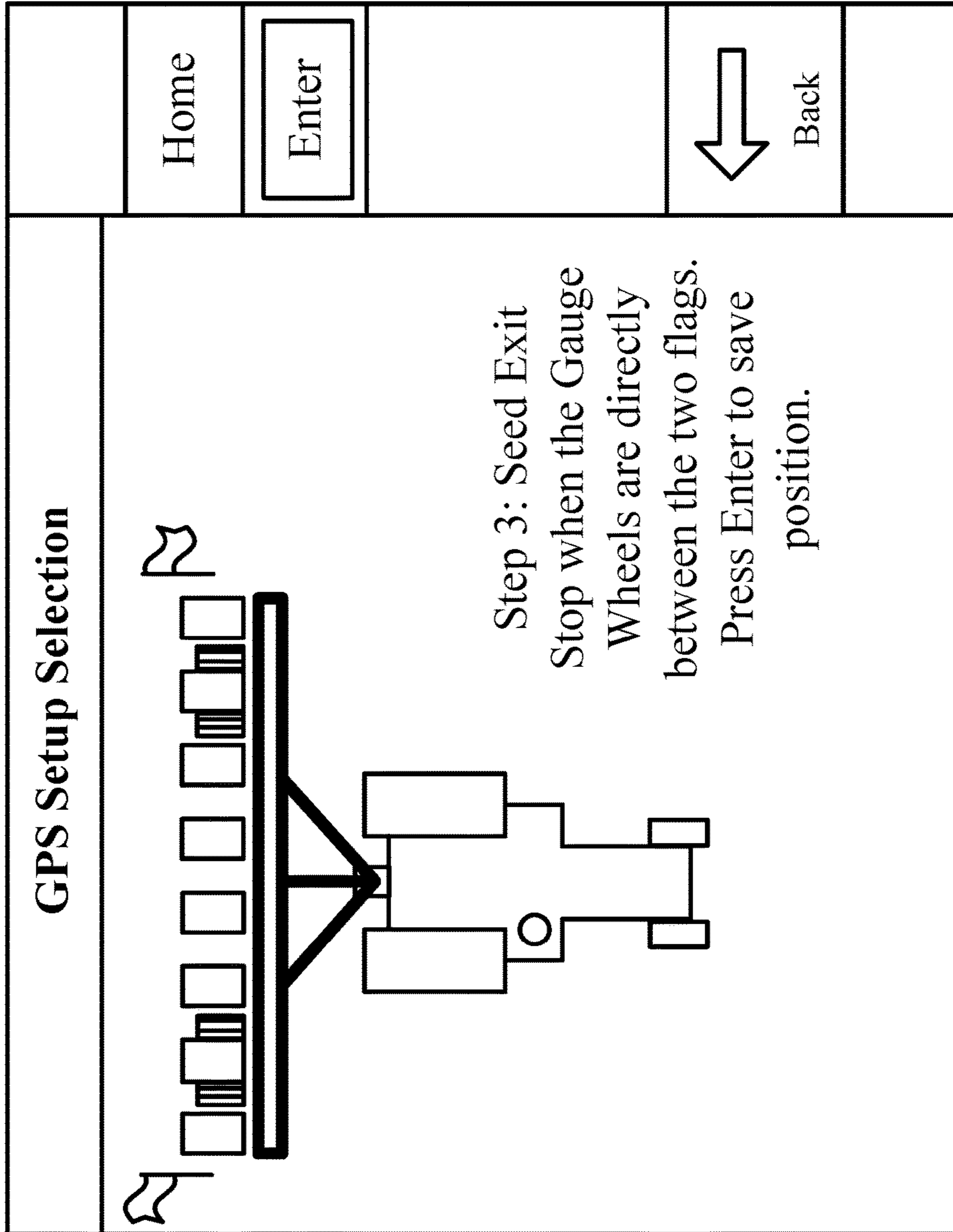


FIG. 10C

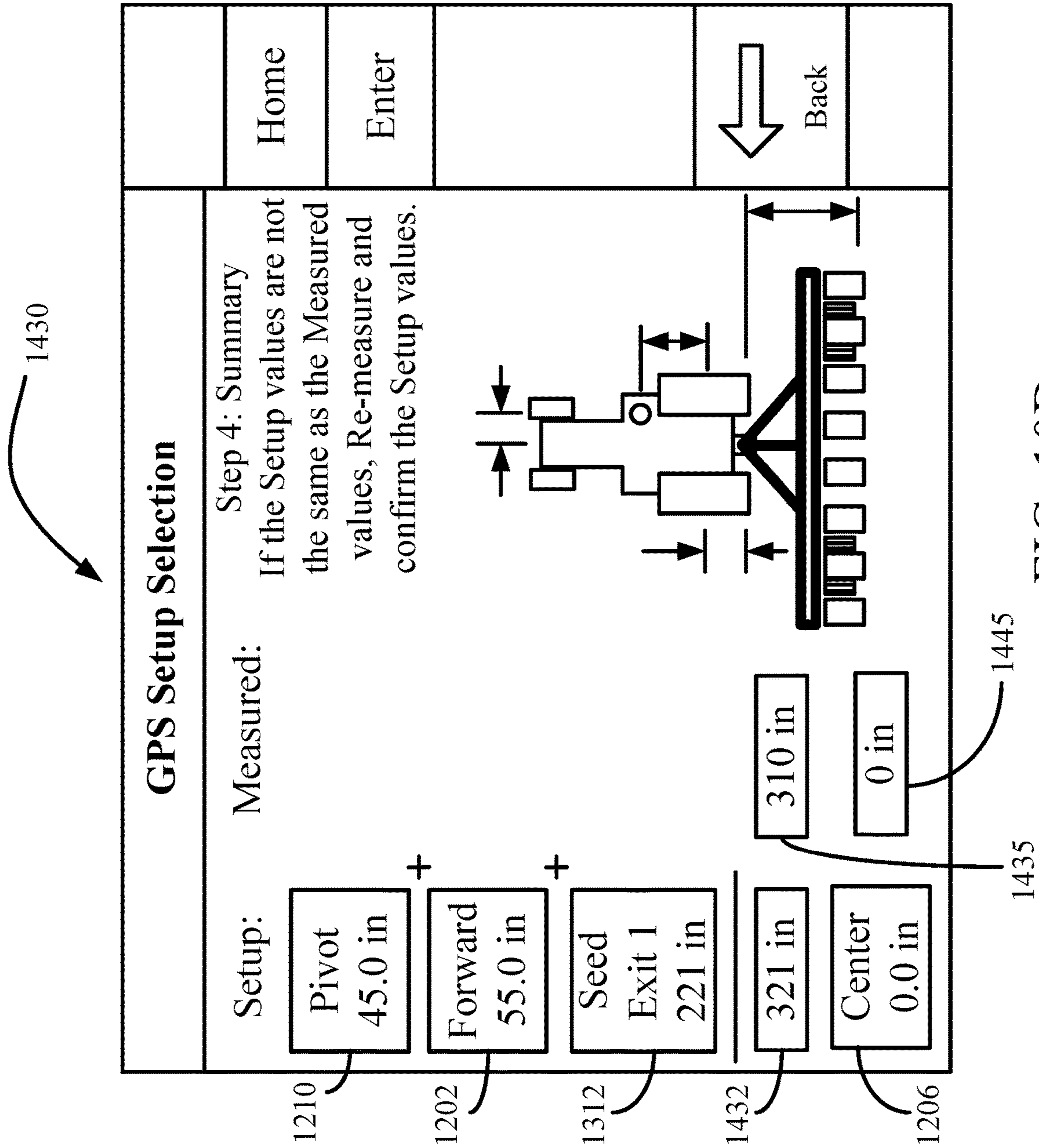
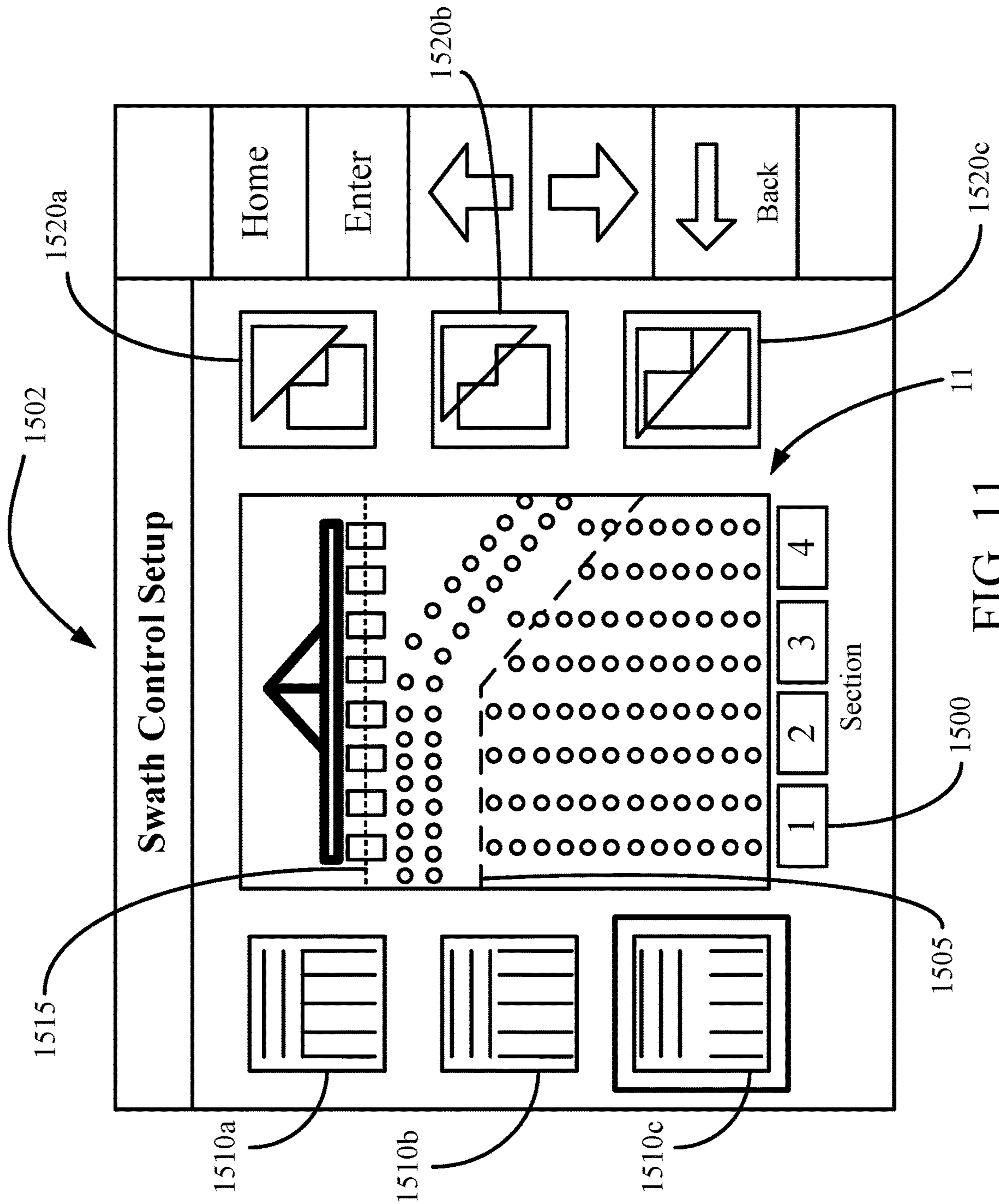


FIG. 10D



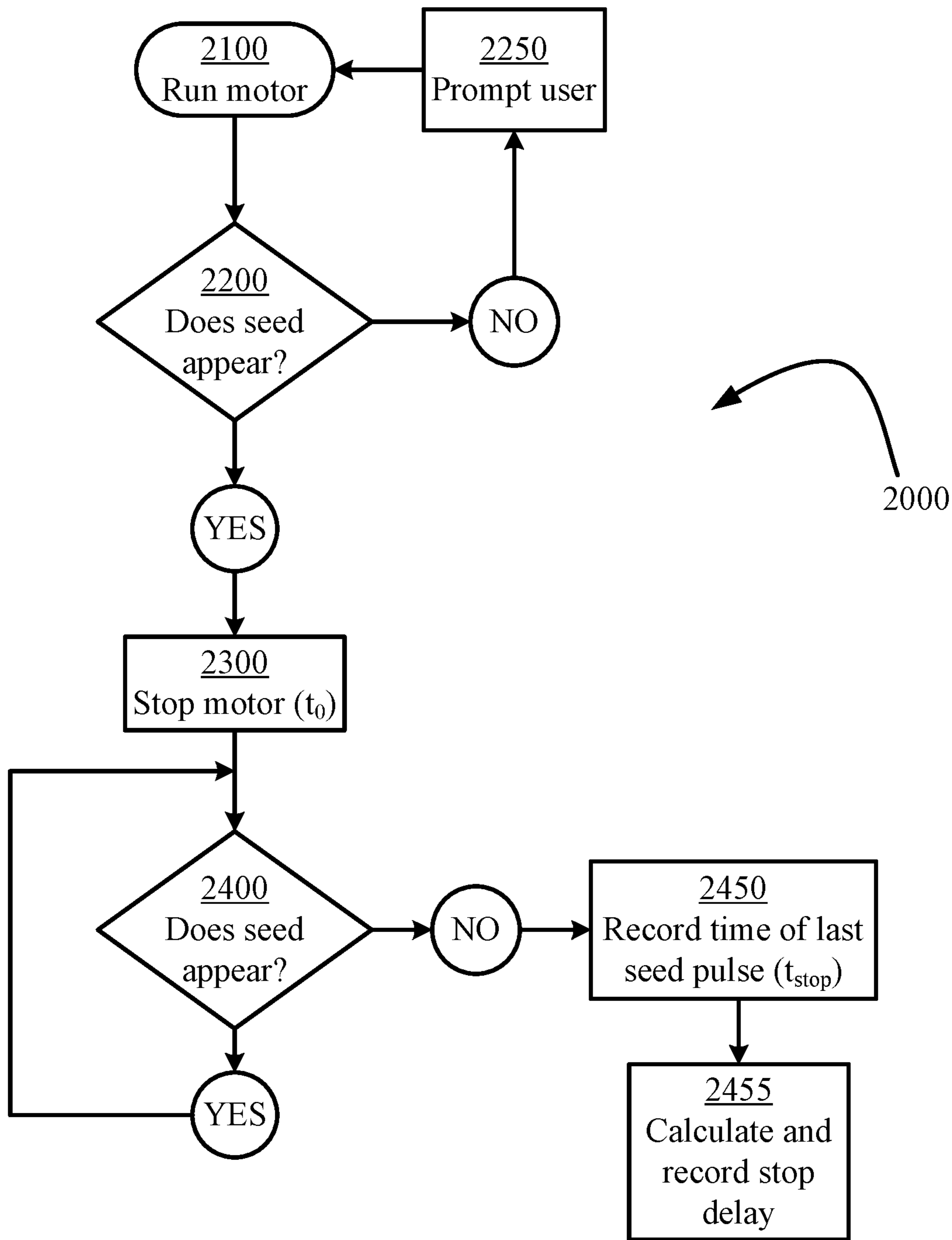


FIG. 12

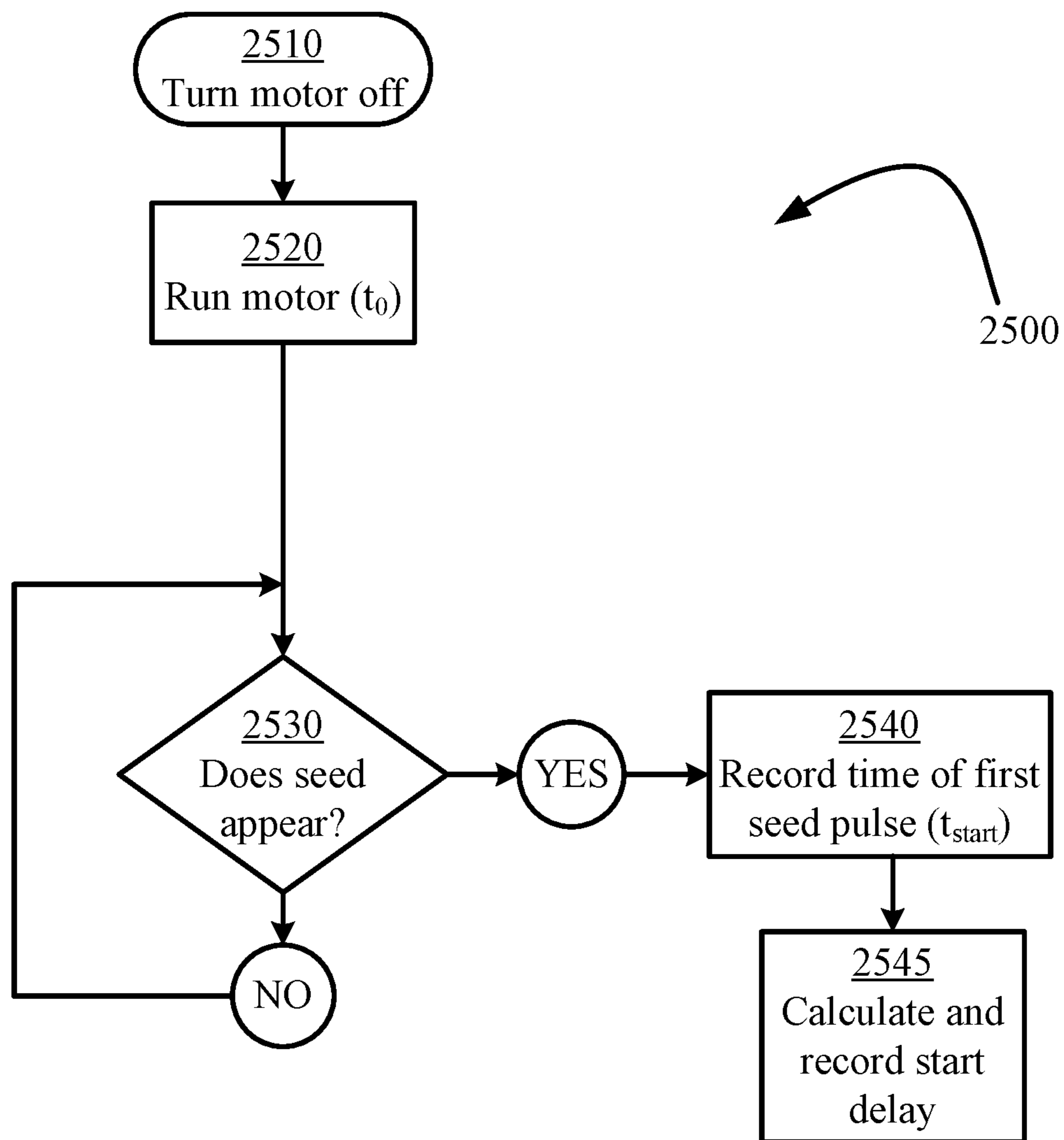


FIG. 13A

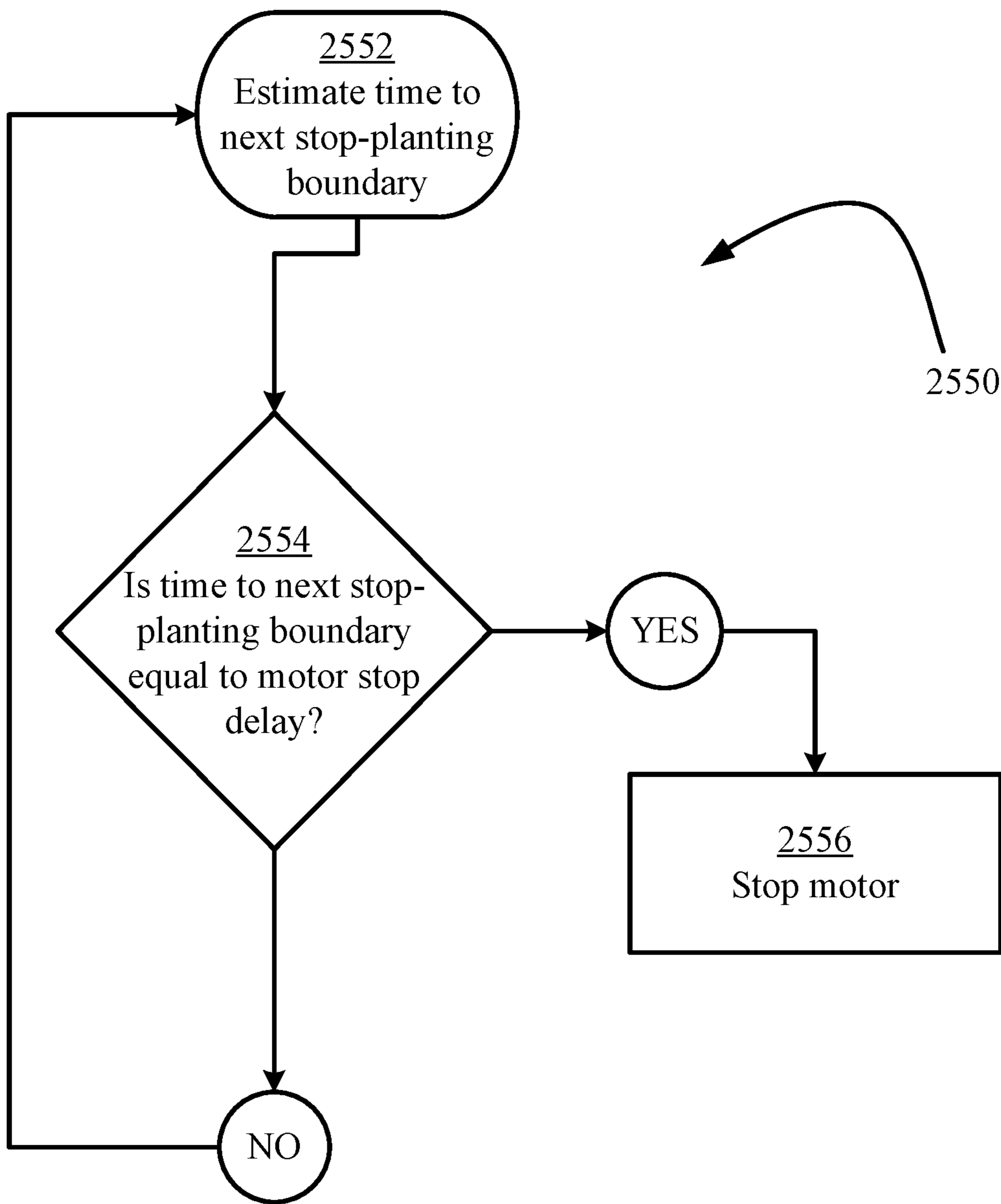


FIG. 13B

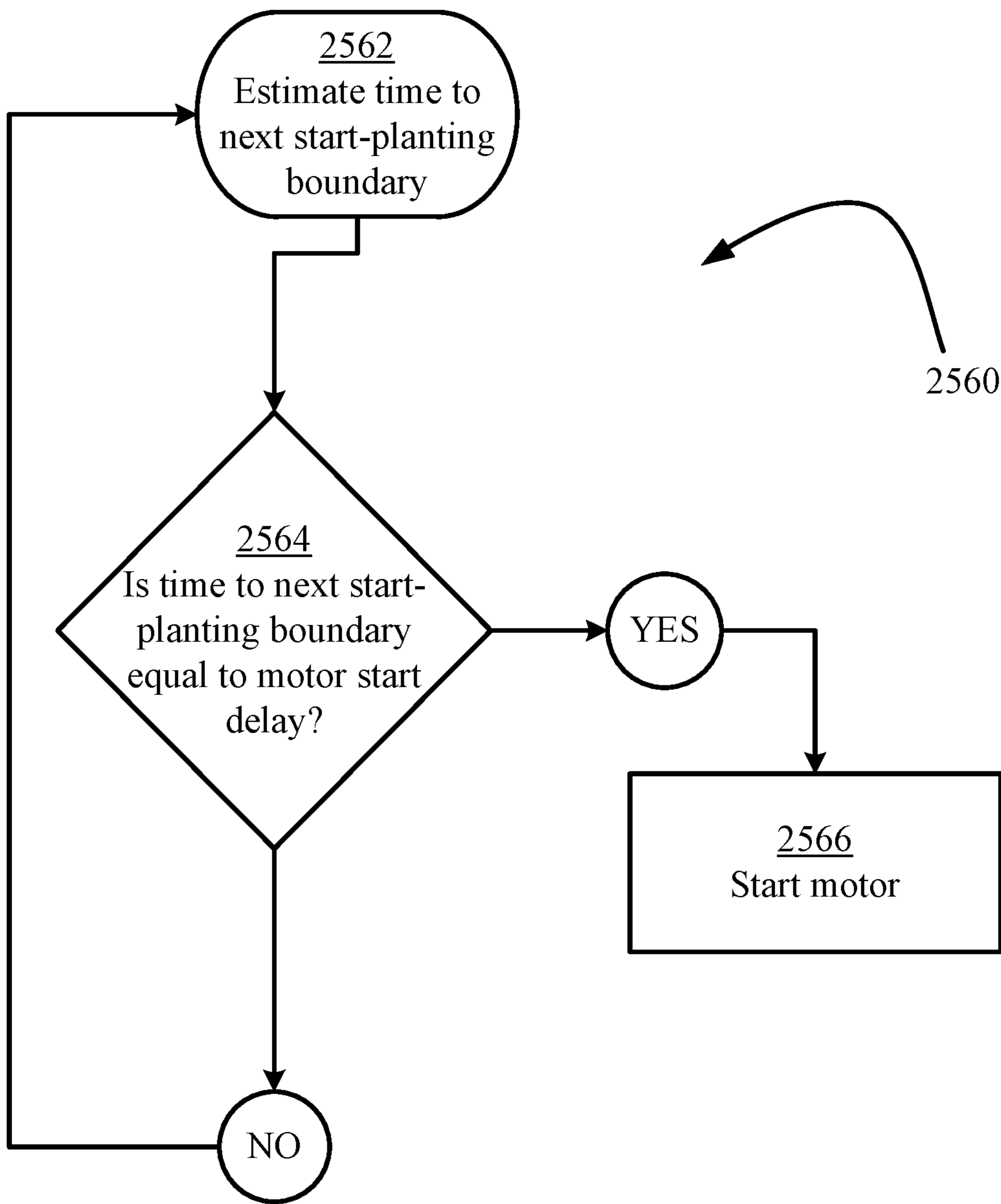


FIG. 13C

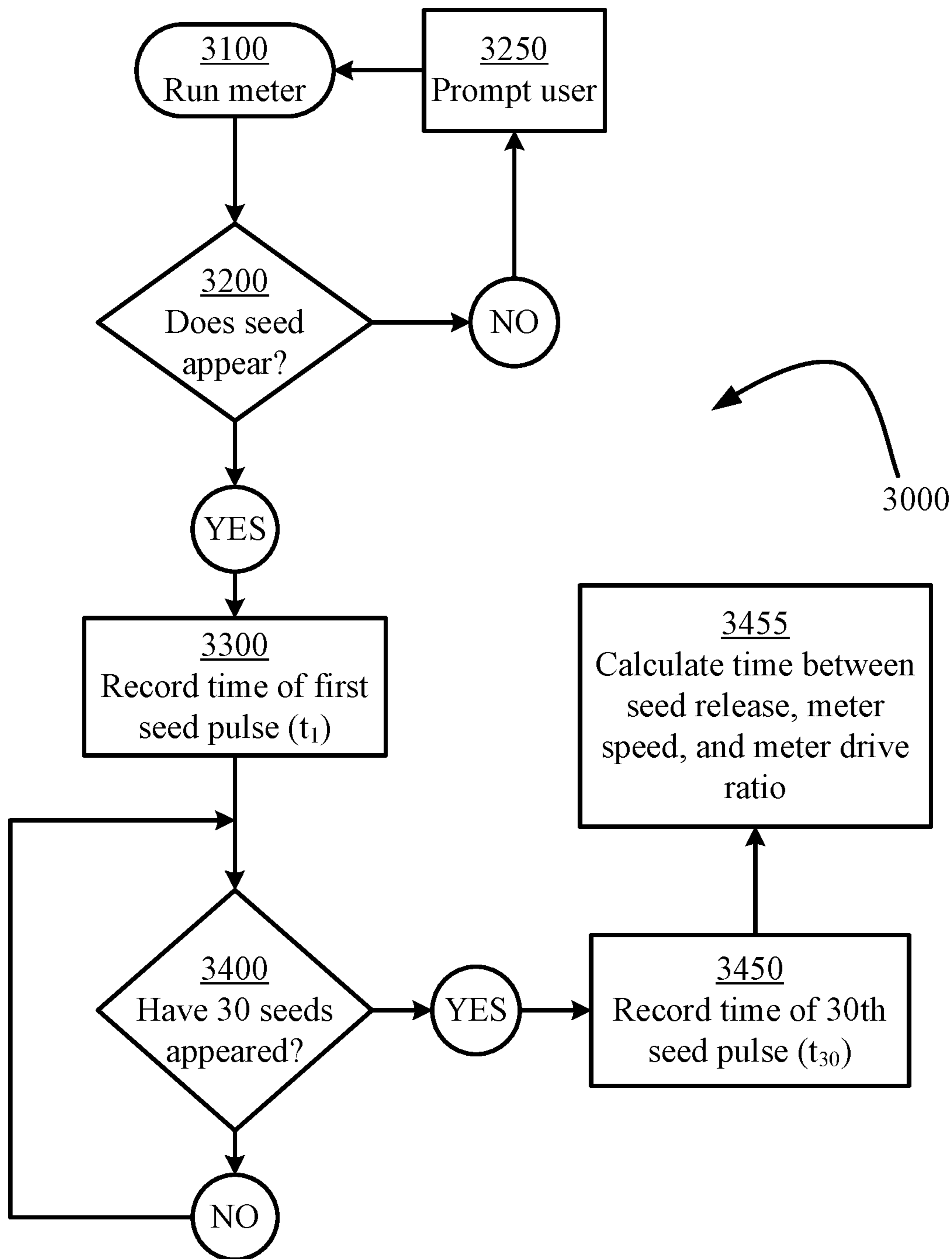


FIG. 14

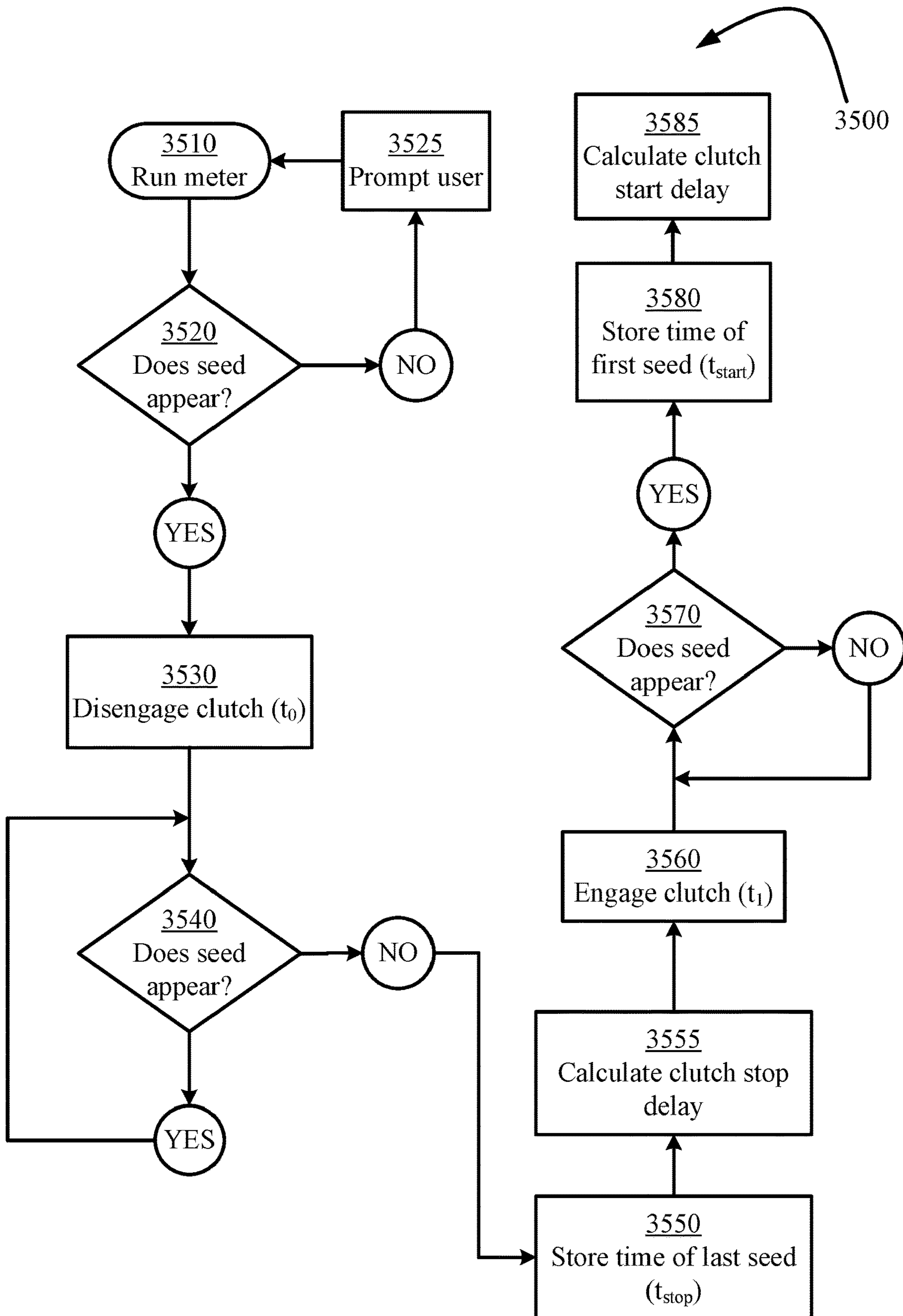


FIG. 15A

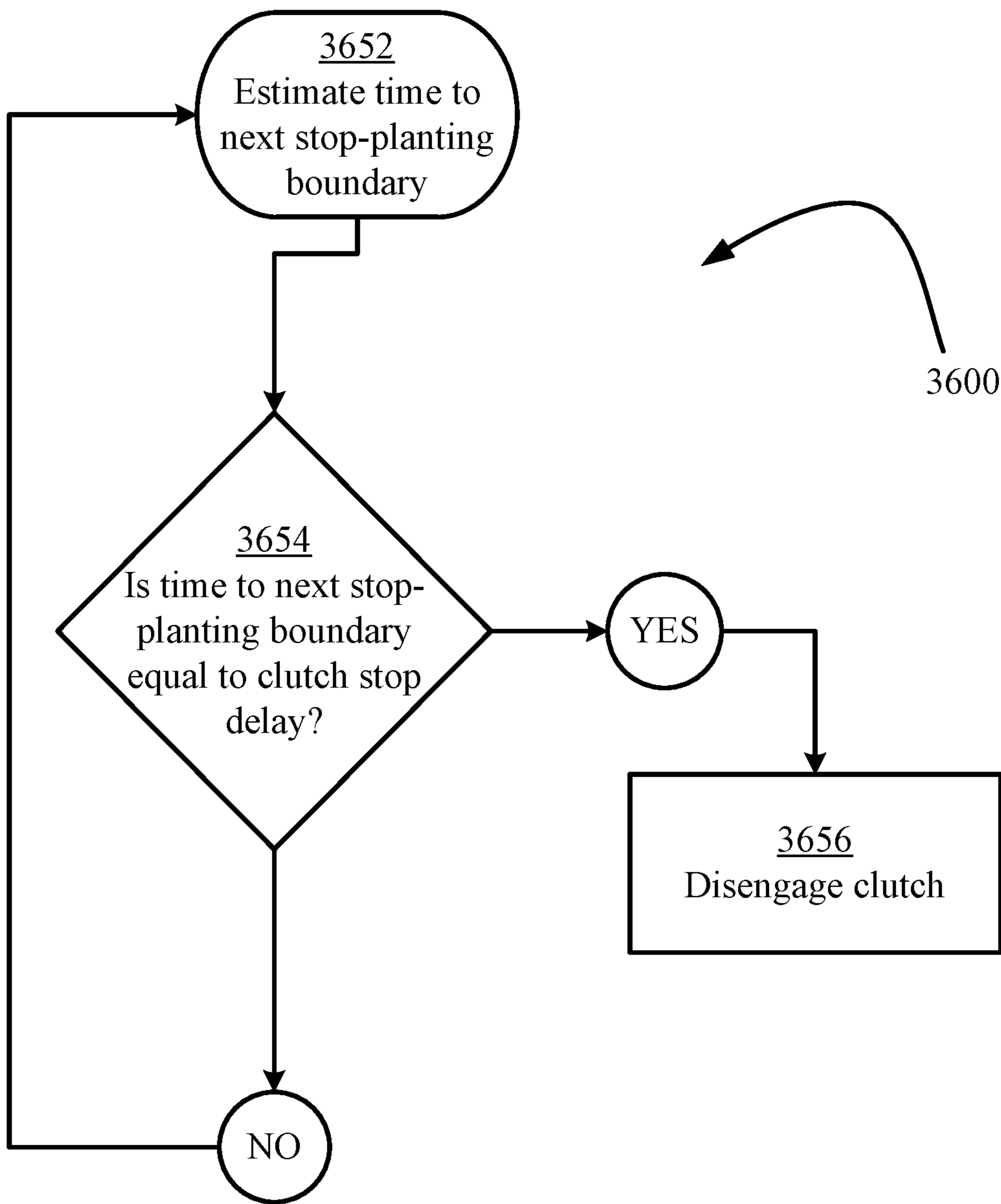


FIG. 15B

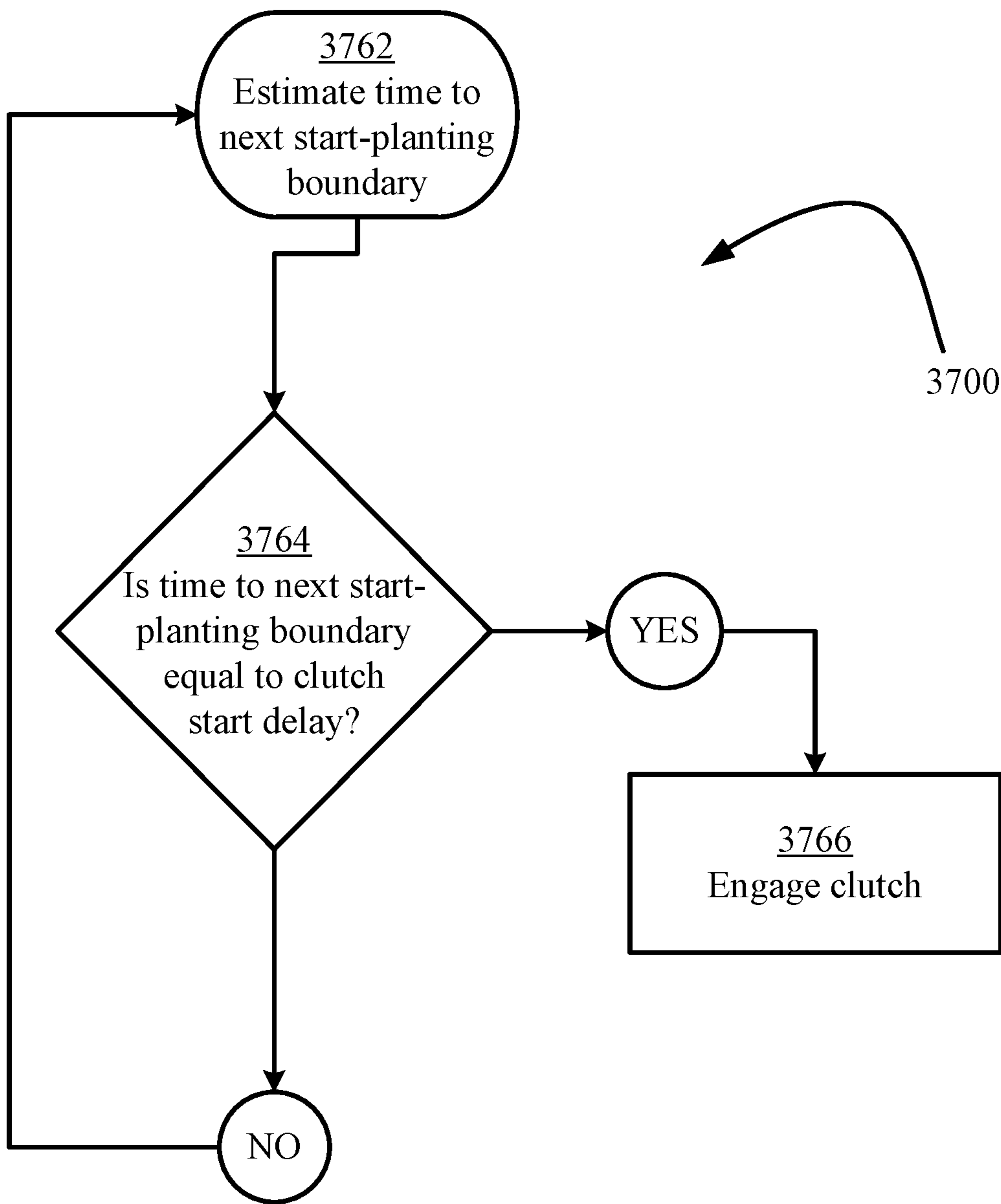


FIG. 15C

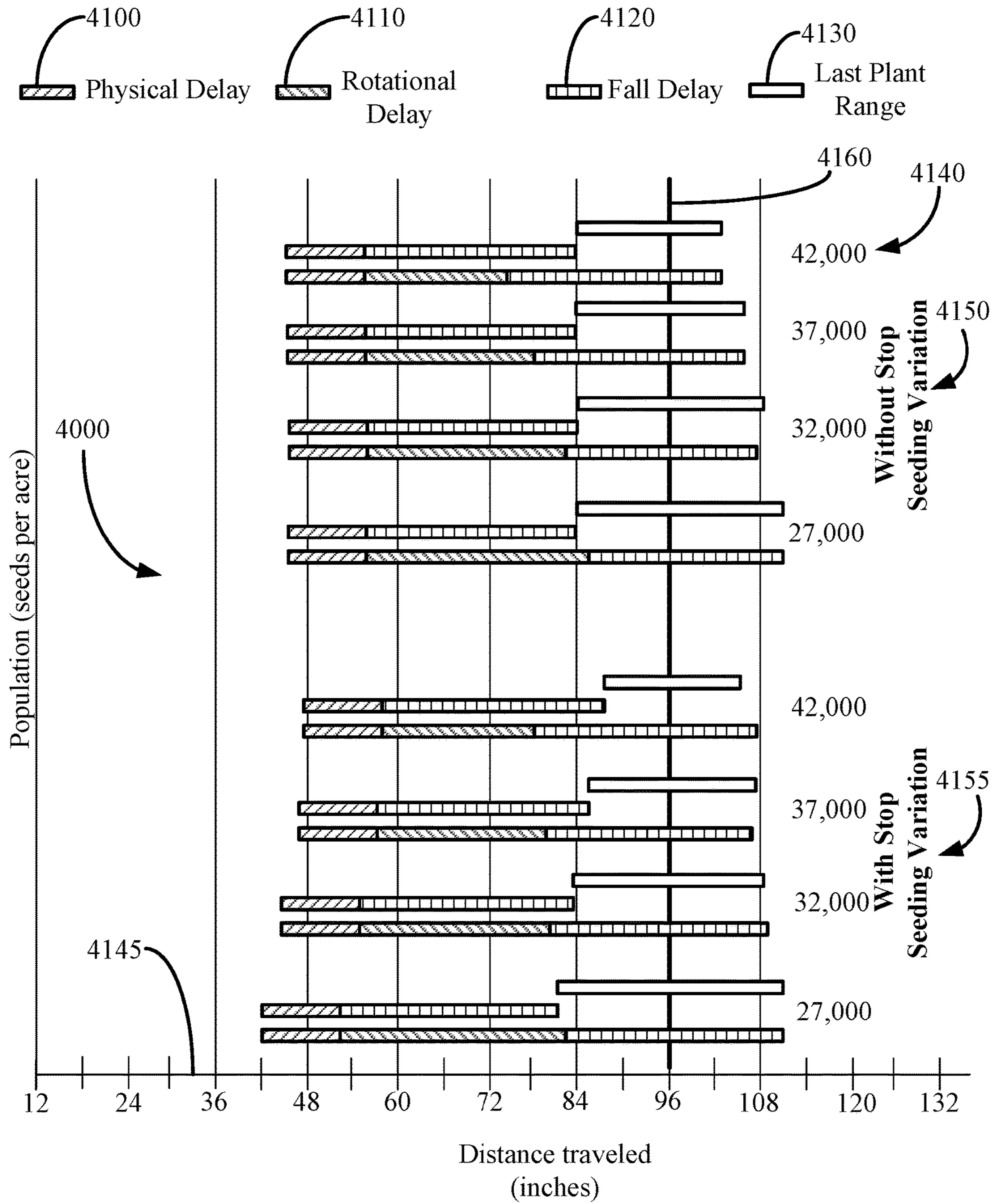


FIG. 16A

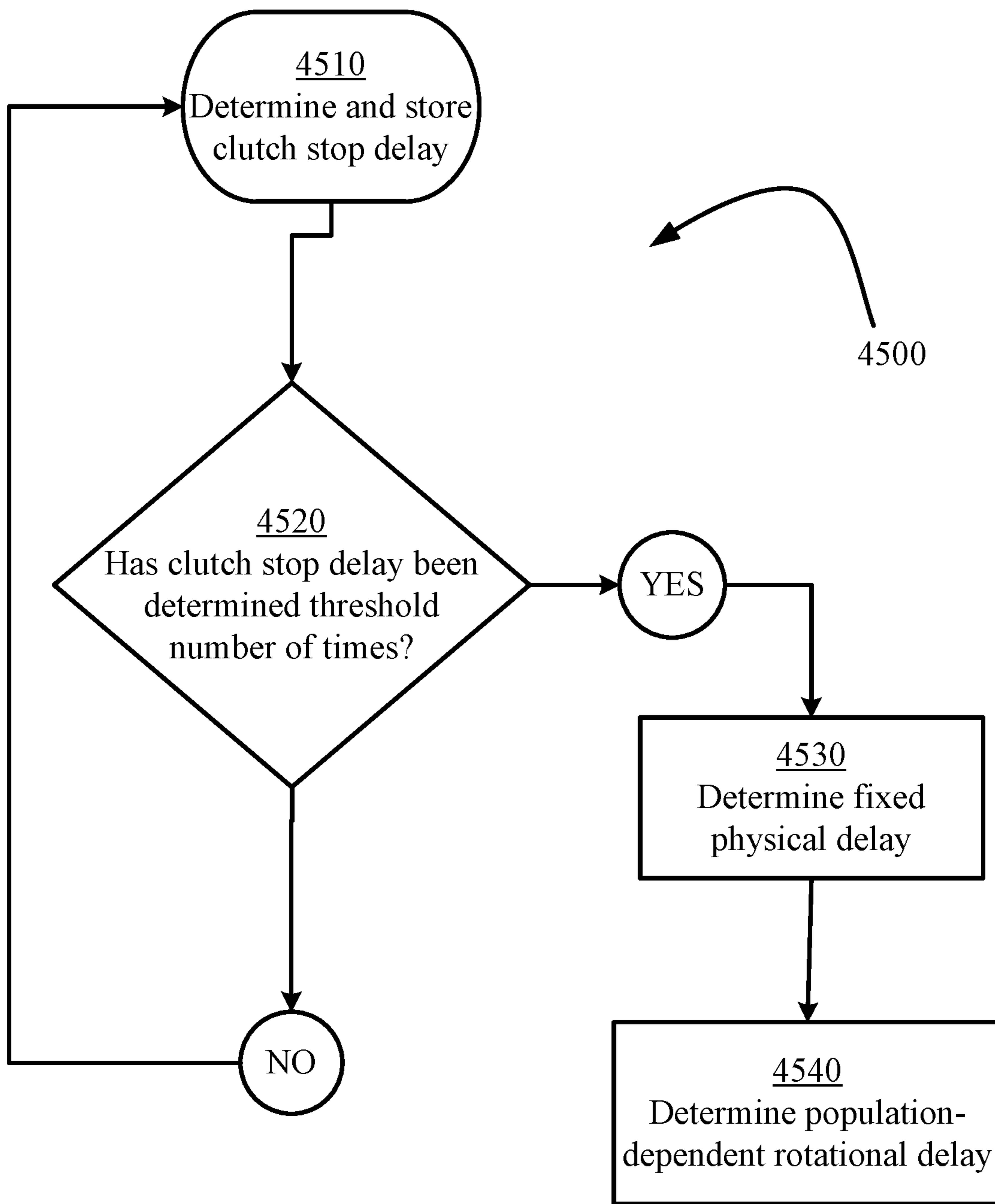


FIG. 16B

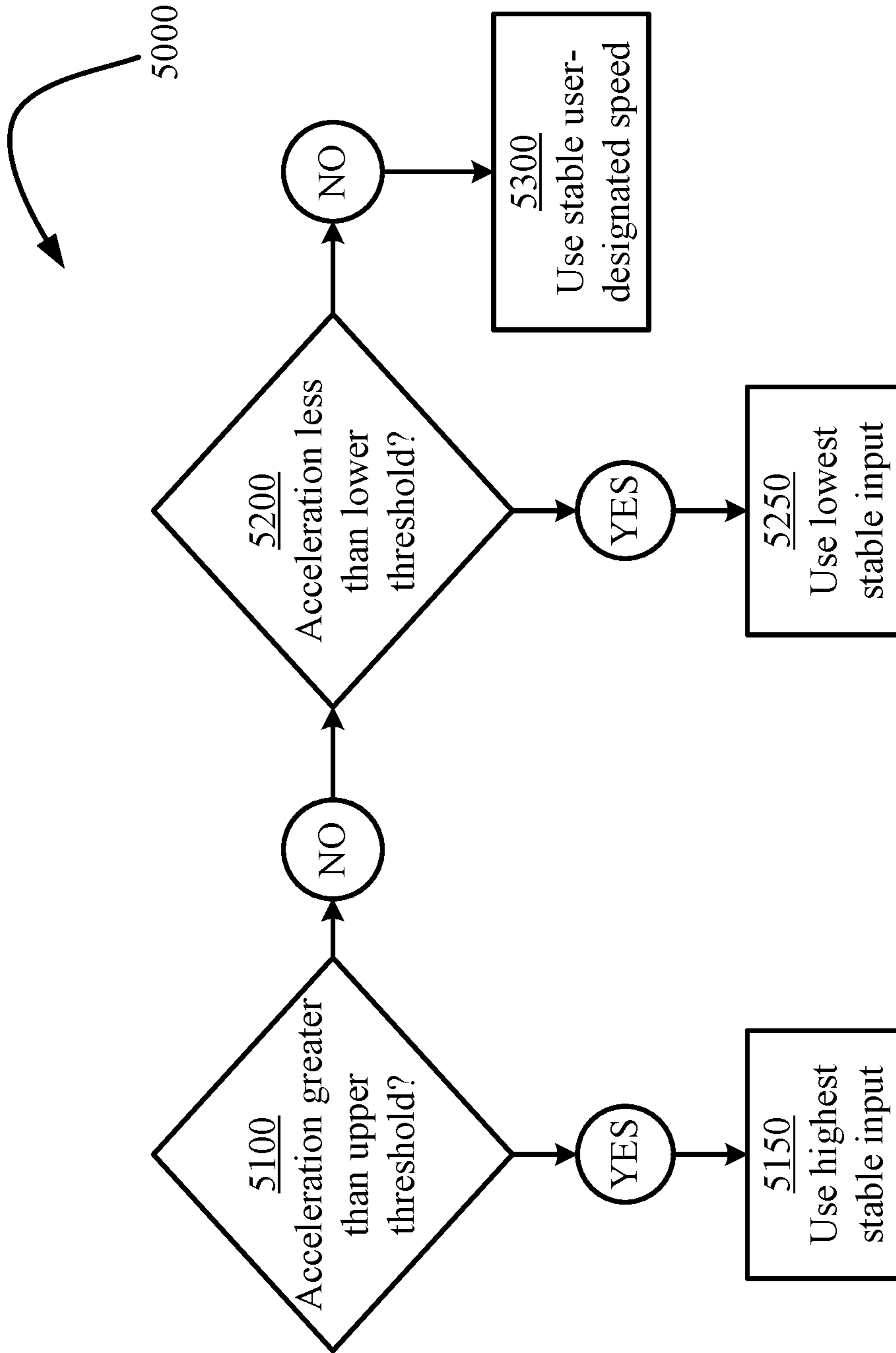


FIG. 17A

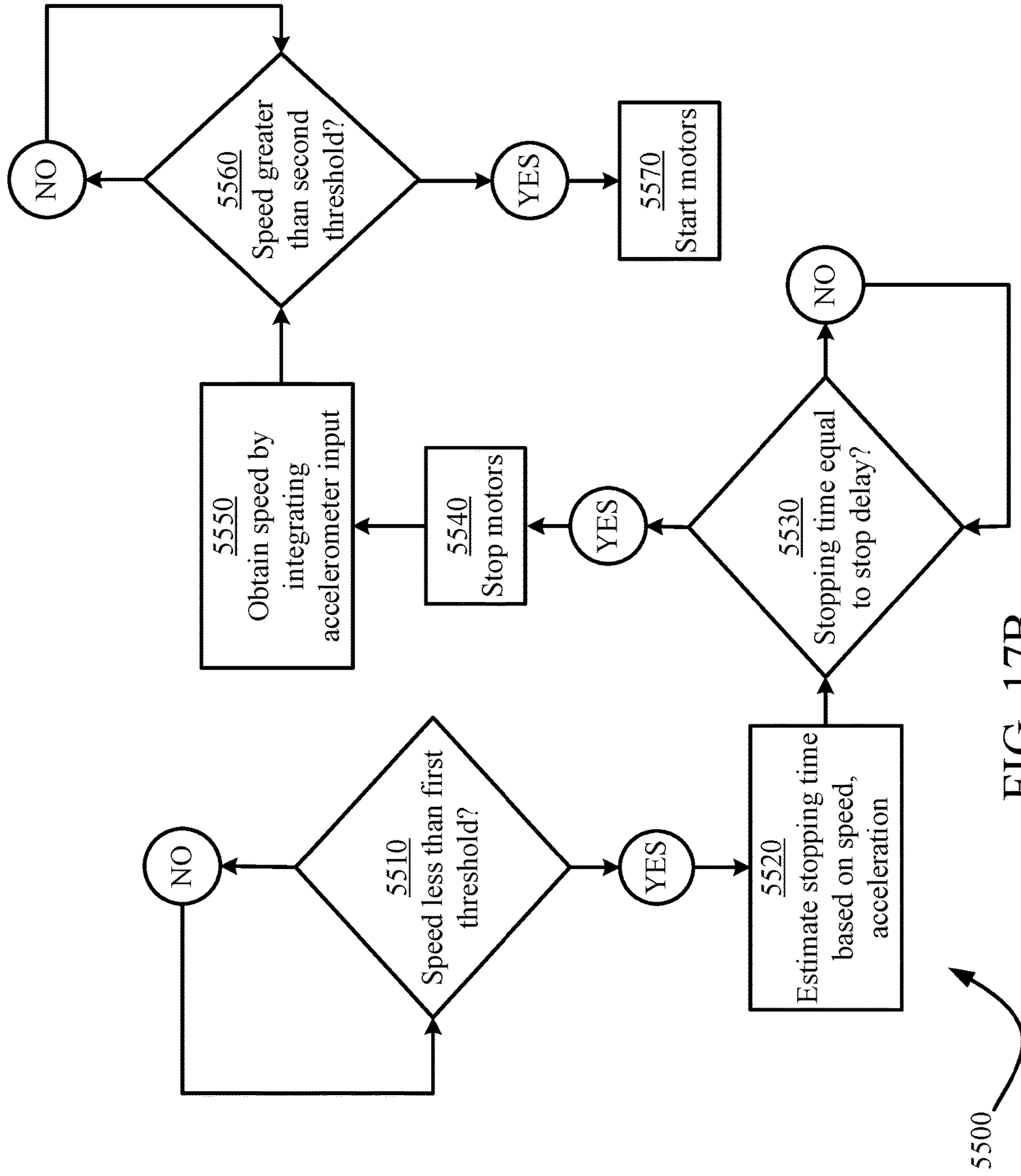


FIG. 17B

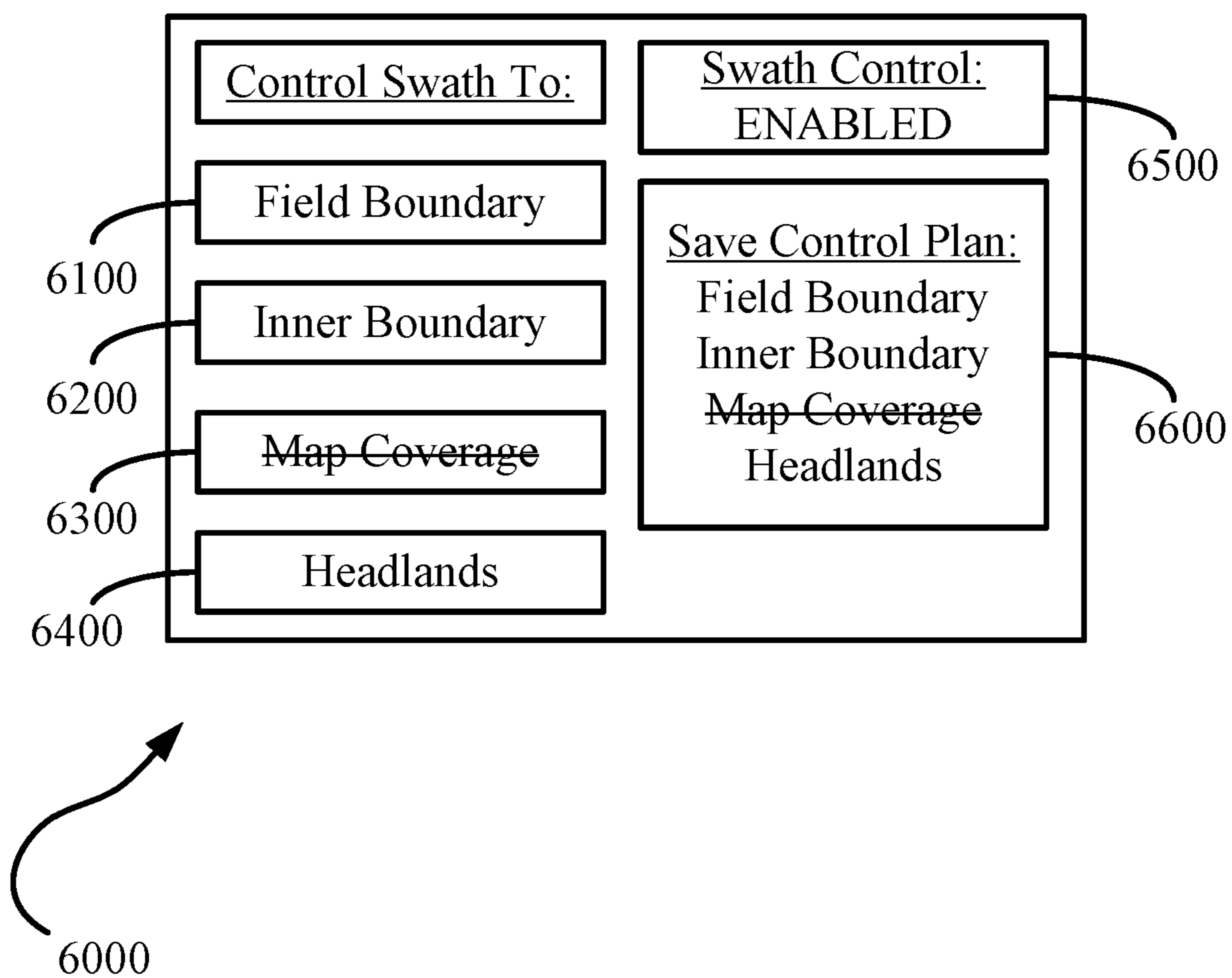


FIG. 18

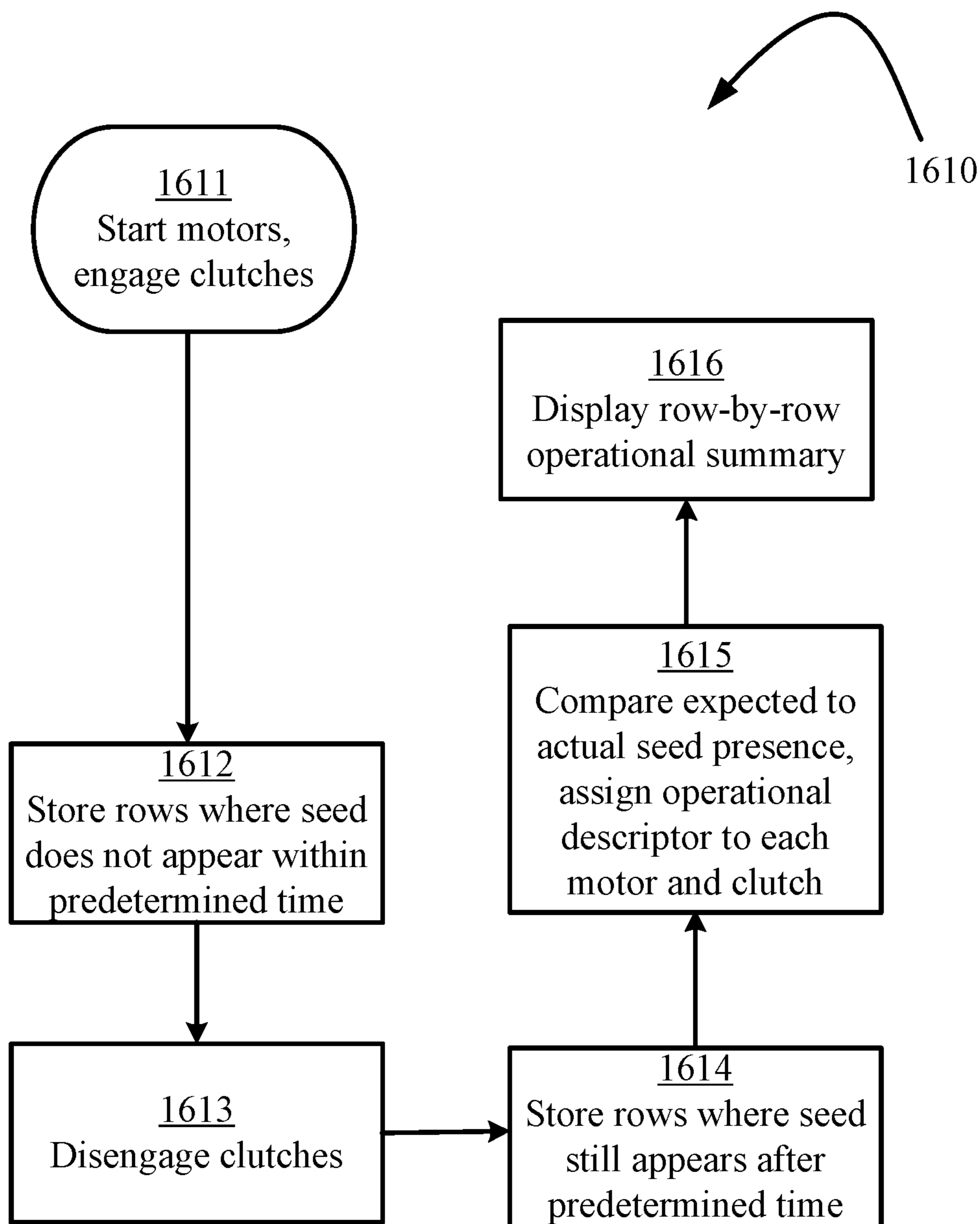


FIG. 19A

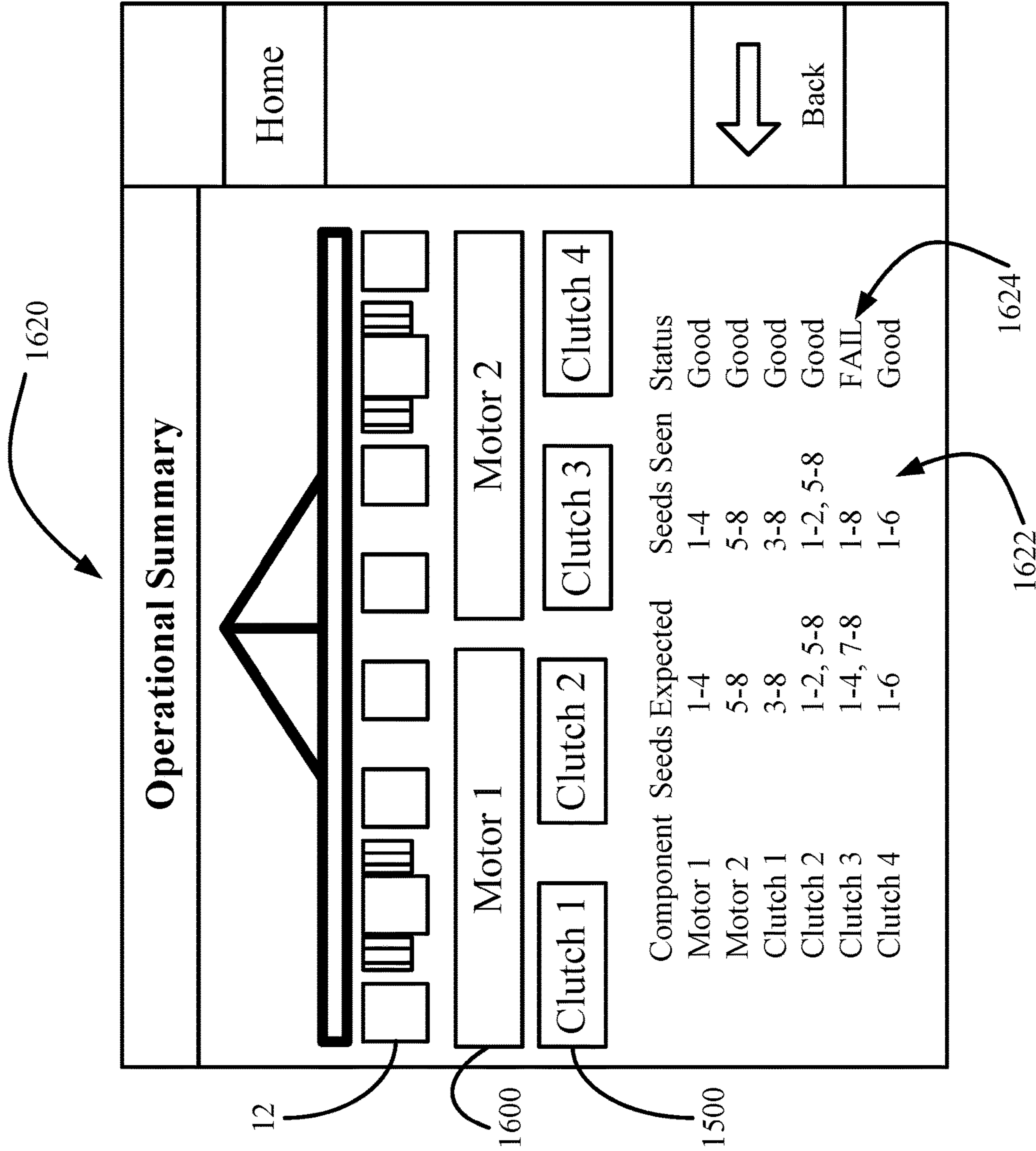


FIG. 19B

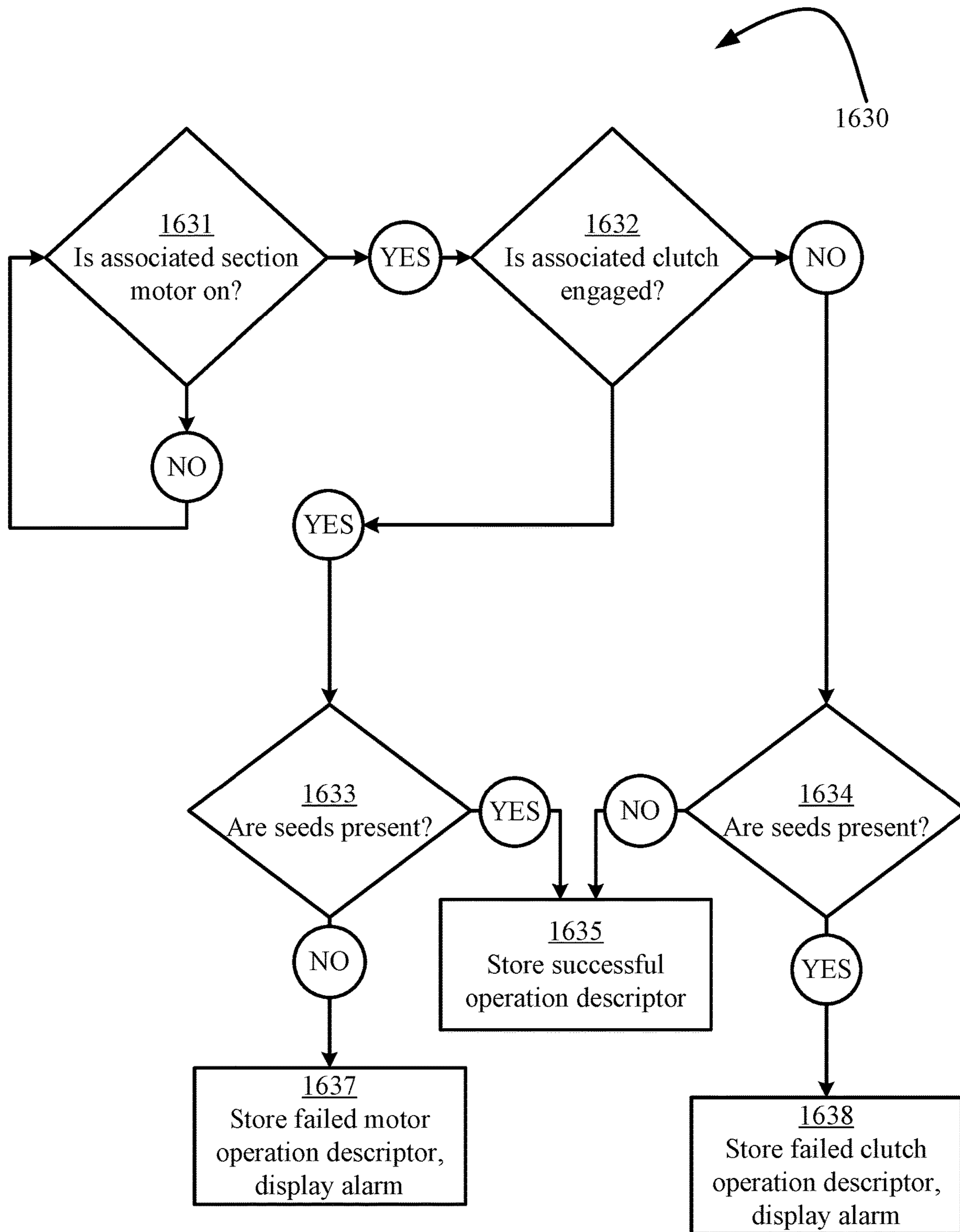


FIG. 19C

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SEEDING CONTROL SYSTEM AND
METHODCROSS-REFERENCE TO RELATED
APPLICATIONS

This application is a continuation of U.S. patent application Ser. No. 13/812,483, filed Jan. 25, 2013, which is a National Stage of International Patent Application No. PCT/US2011/045587, filed Jul. 27, 2011, which claims the benefit of U.S. Provisional Application No. 61/368,117, filed Jul. 27, 2010, each of which is incorporated herein by reference.

BACKGROUND

Planters with variable rate seeding (“VRS”) control systems which allow the seeding rate to be varied while on-the-go based on soil type and soil conditions are well known in the art. Likewise, it is also well known in the planter art to provide “swath control” systems to start and stop seeds being planted in individual rows or sets of rows while on-the-go to minimize overplanting in point rows or underplanting when entering or exiting headlands, around waterways and field boundaries.

Currently available VRS and swath control systems cooperate with Global Position Systems (“GPS”) and field coverage maps to control the seed meter by engaging and disengaging drive clutches so as to control the rotation and/or speed of rotation of the seed disc for vacuum meters or the rotation of the fingers for finger pick-up meters. However, such systems rely on planter location at the time commands are sent to the VRS and swath control systems rather than accurately determining when the seed is actually physically placed in the field. As a result, significant overplanting, underplanting or other inaccuracies can still occur with planters equipped with VRS and swath control systems which rely solely on GPS and coverage maps. For example, if a farmer starts planting but one or more row units are not dispensing seeds due to a malfunction, the field coverage map will show that the area has been planted even though no seed was actually dispensed. It would then be difficult to truly plant that area once the farmer realized the error.

Accordingly there is a need for an improved seeding control system that provides the advantages of VRS and swath control, but which is based on precise seed placement mapping as opposed to GPS-based coverage mapping to minimize overplanting and underplanting of fields.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 shows an eight-row planter without swath control illustrating underplanting of a headland.

FIG. 2 shows an eight-row planter without swath control illustrating overplanting of a headland.

FIG. 3 shows an eight-row planter without swath control illustrating 50/50 underplanting-overplanting of a headland.

FIG. 4 shows an eight-row planter with 1-row swath control illustrating ideal planting with no overplanting or underplanting of a headland.

FIG. 5 A shows an eight-row planter illustrating underplanting with a 2-row swath control system.

FIG. 5B shows an eight-row planter illustrating overplanting with a 2-row swath control system.

FIG. 5C shows an eight-row planter illustrating 50/50 overplanting-underplanting with a 2-row swath control system.

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FIG. 6 shows a field with an inner boundary illustrating different seed populations planted using a VRS with 1-row swath control.

FIG. 7 is a schematic illustration of an embodiment of seeding control system.

FIG. 8 illustrates an embodiment of a monitor screen for entering GPS offsets with respect to a tractor.

FIG. 9 illustrates an embodiment of a monitor screen for entering offsets with respect to a pivot axis of a planter.

FIG. 10A illustrates an embodiment of a monitor screen for beginning a GPS offset verification routine.

FIG. 10B illustrates an embodiment of a monitor screen for continuing a GPS offset verification routine.

FIG. 10C illustrates an embodiment of a monitor screen for completing a GPS offset verification routine.

FIG. 10D illustrates an embodiment of a monitor screen for displaying measured and operator-entered GPS offsets.

FIG. 11 illustrates an embodiment of a monitor screen for configuring swath controllers by selecting a coverage pattern.

FIG. 12 is a schematic illustration of an embodiment of a method of determining a variable rate drive stop delay.

FIG. 13A is a schematic illustration of an embodiment of a method of determining a variable rate drive start delay.

FIG. 13B is a schematic illustration of an embodiment of a method of stopping a variable rate drive based on a variable rate drive stop delay.

FIG. 13C is a schematic illustration of an embodiment of a method of starting a variable rate drive based on a variable rate drive start delay.

FIG. 14 is a schematic illustration of an embodiment of a method of determining a drive ratio between a seed meter and a variable rate drive.

FIG. 15A is a schematic illustration of an embodiment of a method of determining a start delay and a stop delay of a swath controller.

FIG. 15B is a schematic illustration of an embodiment of a method of disengaging a swath controller based on a swath control stop delay.

FIG. 15C is a schematic illustration of an embodiment of a method of engaging a swath controller based on a swath control start delay.

FIG. 16A is a graph of empirical data illustrating various delays associated with a swath controller.

FIG. 16B is a schematic illustration of an embodiment of a method of determining components of a swath control stop delay.

FIG. 17A is a schematic illustration of an embodiment of a method of selecting a speed input.

FIG. 17B is a schematic illustration of an embodiment of a method of stopping and starting a variable rate motor based on acceleration.

FIG. 18 is a schematic illustration of an embodiment of a user interface screen used to select stop-planting conditions.

FIG. 19A is a schematic illustration of an embodiment of a method of identifying an operational problem with a seeding control system.

FIG. 19B illustrates an embodiment of a monitor screen for displaying an operational summary of a seeding control system.

FIG. 19C is a schematic illustration of another embodiment of a method of identifying an operational problem with a seeding control system.

DESCRIPTION

Referring now to the drawings, wherein like reference numerals designate identical or corresponding parts

throughout the several views, FIGS. 1-5 show a planter 10 planting seeds 11 in a field 13 in which the headland 15 has been previously planted. FIGS. 1-5 are intended to illustrate for comparison purposes “overplanting” and “underplanting” planting techniques using an eight-row planter without swath control (FIGS. 1-3) and then with swath control (FIGS. 4-5).

FIG. 1 shows an eight-row planter without swath control overplanting the headland 15 (i.e., where planting continues across all rows until the last row is within the headland 15). FIG. 2 illustrates an eight-row planter without swath control underplanting the headland 15 (i.e., where planting stops across all rows as soon as the first row enters the headland 15). FIG. 3 shows an eight-row planter without swath control illustrating 50/50 underplanting-overplanting of the headland 15 (i.e., where planting continues across all rows until half of the rows enter the headland 15). It should be understood that the opposite occurs when exiting a headland. That is, when exiting a headland using the overplanting technique, planting begins across all rows as soon as the first row of the planter exits the headland. Likewise, when exiting a headland using the underplanting technique, planting does not begin across all rows until the last row exits the headland. With the 50/50 technique, planting begins across all rows when half of the rows exit the headland.

FIG. 4 shows an eight-row planter with swath control on every row of the planter (hereinafter a “1-row swath control”). FIGS. 5A-5C illustrate an eight-row planter with swath control for every two rows of the planter (hereinafter a “2-row swath control”). It should be appreciated that swath control may include any desired number of rows. Comparing FIGS. 1-3 with FIG. 4, one can clearly see that a 1-row swath control system will ideally plant a field with little or no overplanting or underplanting thereby minimizing wasted seed and unplanted areas resulting in improved yield, all other factors being equal. Similarly, comparing FIGS. 1-3 with FIGS. 5A, 5B and 5C, one can clearly see that a 2-row swath control system will ideally plant a field with only minimal overplanting or underplanting when compared to conventional planters without swath control.

FIG. 6 shows a field 13 having two different soil types 15, 17 designated by different hatch patterns, separated by an inner boundary 19. The different soil types are shown planted with different seed populations (note different spacing of seeds 11 between the different soil types 15,17) using a planter with VRS and 1-row swath control wherein as each row unit passed the inner boundary 19, the VRS was engaged to change the seed population to the different soil type.

It should be appreciated, however, that even if the planter is equipped with a swath control system, unless precise seed placement is known and unless the swath control system takes into account certain factors, significant overplanting and underplanting can still take place if these factors are not taken into consideration. These factors include planter speed, timing delays in starting and stopping of the seed meter, and timing delays between the seed being discharged from the seed meter until the seed passes through the seed tube and into the furrow, and other factors as discussed later. It should also be appreciated that overplanting and underplanting of rows can occur when entering or exiting different soil types with different desired seed populations if these same factors are not taken into account.

General Overview

FIG. 7 illustrates a seeding control system 1005 that cooperates with the row units 12 of a planter 10 to improve

yield by taking the above-identified factors and other factors into consideration for precise mapping of seed placement in the field.

In FIG. 7, the row unit 12 is illustrated as a row unit for a central-fill planter such as disclosed in U.S. Pat. No. 7,438,006, incorporated herein in its entirety by reference, but it should be appreciated that the seeding control system 1005 may be used with more conventional row units such as disclosed in U.S. Pat. No. 4,009,668, also incorporated herein in its entirety by reference, or any other type of row unit for any make or model of a planter. The row units 12 are spaced along a toolbar 14 of the planter main frame. The planter main frame is attached to a tractor (not shown) in a conventional manner, such as by a drawbar or three-point hitch arrangement as is well known in the art. Ground wheel assemblies (not shown) support the main frame above the ground surface and are moveable relative to the main frame through actuation of the planter’s hydraulic system (not shown) coupled to the tractor’s hydraulics to raise and lower the planter main frame between a transport position and a planting position, respectively.

Each row unit 12 is preferably supported from the toolbar 14 by a parallel linkage 16 which permits each row unit 12 to move vertically independently of the toolbar 14 and the other spaced row units in order to accommodate changes in terrain or upon the row unit encountering a rock or other obstruction as the planter is drawn through the field. Each row unit 12 includes a seed meter 30, a seed tube or other seed path 32, a furrow opening assembly 34 and a furrow closing assembly 36. The furrow opening assembly cuts a furrow 38 into the soil surface 40 as the planter 10 is drawn through the field. A constant supply of seed 11 is communicated to the seed meter 30. The seed meter 30 discharges individual seeds 11 into the seed tube 32 at spaced intervals based on the seed population desired and the speed at which the planter is drawn through the field. The seed 11 drops from the end of the seed tube 32 into the furrow 38 formed by the furrow opening assembly 34. The seeds 11 are then covered with soil by the closing wheel assembly 36.

In operation, as each seed 11 passes through the seed tube 32, the seed sensor 200 sends a seed pulse to the planter monitor 1000. The planter monitor 1000 associates the time of the seed pulse with a location of the GPS unit 100 to determine the precise location of the planted seed within the field by taking into account the planter speed, seed population, offset distances, etc., all previously determined and calibrated during setup and calibration phases (discussed later) to generate a precise seed placement map. Based on the generated seed placement map, the planter monitor 1000 will determine if a “stop-planting” condition exists when a row unit or swath (i.e. one or more row units controlled by a swath controller 1500) of the planter 10 passes over a previously planted seed or when a row unit or swath travels across a headland, an outer boundary or an inner boundary of the field. If a stop-planting condition exists for a particular row unit or swath, a signal will be generated to disengage a clutch taking into account various factors such as planter speed, changes in acceleration, clutch delays, seed drop delays, etc., all previously determined and calibrated during the setup and calibration phases (discussed later) such that the corresponding seed meters cease dispensing seed at the appropriate time and to resume dispensing seed at the appropriate time after the “stop planting” condition has passed so as to ensure minimal overplanting or underplanting of the field.

Preferred Seeding Control System Components

The seeding control system 1005 preferably includes a GPS (global positioning system) unit 100, seed sensors 200,

a control unit **350**, and height sensors **705**, a planter monitor **1000**, a cab module **1105** and a radar system **1205** which cooperate to control a variable rate drives **1600** and swath controllers **1500** of the planter **10** to minimize overplanting and underplanting of fields.

The planter monitor **1000** is typically mounted in the tractor cab so it can be easily viewed and interfaced with by the operator while planting. A preferred planter monitor **1000** is the 20/20 SeedSense® from Precision Planting, Inc., 23207 Townline Road, Tremont, Ill. 61568 and as disclosed in published U.S. patent application Pub. No. US 2010/0010667, incorporated herein in its entirety by reference. The planter monitor preferably utilizes a touch screen graphic user interface (GUI) and includes microprocessor, memory and other applicable hardware and software for receiving, storing, processing, communicating, displaying and performing the various features and functionalities as hereinafter described (hereinafter, collectively, the “processing circuitry”) as readily understood by those skilled in the art. The planter monitor **1000** is preferably configured to communicate with a data transfer device such as a USB flash drive, internet connection or any other data transfer means for input and retrieving seed population rates, field mapping information, etc. In addition, the planter monitor **1000** is in electrical communication (via wires or wirelessly) to receive input signals from the seed sensors **200**, a GPS unit **100** and the cab module **1105**.

Seed sensors **200** are mounted to the seed tubes **32** of the row units **12** to detect the passage of seed therethrough. A common seed sensor **200** is a photoelectric sensor, such as manufactured by Dickey-John Corporation, 5200 Dickey-John Road, Auburn, Ill. 62615. A typical photoelectric sensor generally includes a light source element and a light receiving element disposed over apertures in the forward and rearward walls of the seed tube. In operation, whenever a seed passes between the light source and the light receiver, the passing seed interrupts the light beam causing the sensor **200** to generate a seed pulse or electrical signal indicating the detection of the passing of a seed. It should be appreciated that any type of seed sensor capable of producing an electrical signal to designate the passing of a seed may be used.

The GPS unit **100** is configured to receive a GPS signal, comprises a series of GPS data strings, from a satellite (not shown). The GPS signal is communicated to the planter monitor **1000**. A preferred GPS unit **100** is a Deluo PMB-288 available from Deluo, LLC, 10084 NW 53rd Street, Sunrise, Fla. 33351, or other suitable device. The GPS unit **100**, is used to monitor the speed and the distances traveled by the planter **10**. As will be discussed in more detail later, preferably the output of the GPS unit **100**, including the planter speed and distances traveled by the planter, is communicated to the planter monitor **1000** for display to the planter operator and/or for use in various algorithms for deriving relevant data used in connection with the preferred system and method of the present invention. In alternative embodiments, the GPS unit **100** comprises a positioning system configured to use the signals of other satellite systems such as GLONASS or Galileo. In still other embodiments, the GPS unit **100** may comprise any other positioning system configured to determine the latitudinal and longitudinal position of the planter **10**.

In addition to a GPS unit, the seeding control system **1005** preferably includes a radar system **1205** to determine a speed of the planter **10** because empirical data has shown that data from the GPS unit **100** is delayed and untrustworthy at speeds lower than approximately one mile per

hour (1 mph). Empirical data has also shown that the GPS unit **100** will indicate speeds of 0.1 or 0.2 mph when the planter **10** is actually stopped. For these reasons, speed inputs provided by GPS systems alone are non-ideal for accurately determining when a planter **10** has stopped or for predicting when the planter will stop (for reasons discussed later) or when determining if the planter **10** has resumed travel. The radar system **1205** is placed in a fixed location and sends a radar signal to the cab module **1105** which in turn communicates the radar signal to the planter monitor **1000** for displaying the planter speed.

The cab module **1105** is preferably mounted in the tractor cab such that it too can be easily viewed and interfaced with by the operator while planting. The cab module **1105** preferably includes switches configured to allow the operator to turn the variable rate drives **1600** on and off and to selectively engage and disengage the swath controllers **1500** during pre-planting calibration routines (discussed later). The cab module **1105** also communication with the radar system **1205** and includes processing circuitry configured to determine whether the radar-reported speed is stable for reasons discussed later.

The height sensors **705** may comprise a contact switch configured to close or open a circuit when the gauge wheel arms of the furrow opening assembly **34** are no longer in contact with the gauge wheel arm stop indicating that the planter is in a transport position or otherwise raised above the soil. In other embodiments, the height sensor **705** may also comprise any sensor mounted to a location on the planter **10** that determines the height of said location relative to the soil surface **40** for purposes of indicating that the row unit is in a transport position or otherwise raised above the soil.

The control unit **350** preferably includes an inclinometer **600**, vertical accelerometer **500**, a horizontal accelerometer **400** and appropriate processing circuitry all physically integrated into a single unit that is preferably mounted to the toolbar **14** of the planter **10**, but which may be mounted in other suitable location and in any orientation appropriate to measure the horizontal acceleration, vertical acceleration, and inclination of the tractor and/or toolbar **14**. The control unit **350** is in electrical communication (via wires or wirelessly) with the swath control **1500**, the variable rate drives **1600**, the height sensors **705** and the cab module **1105**. More than one control unit **350** may be utilized.

Setup

In a setup phase, the operator is preferably able to select the tractor make and model and the planter make and model preferably through drop down selection menus. The geometry of the various tractor and planter makes and models are preferably stored in memory to make the setup phase quicker and easier so the operator does not have to physically measure each of the various distances discussed below for modeling the geometry of the planter and the offset distances to the GPS unit **100**. The seeding control system **1005** uses these distances to determine the location of each seed sensor **200** based on a location of the GPS unit **100**. The following method and illustrations assume that the GPS unit **100** is mounted on the tractor cab, although it should be appreciated that other mounting locations (such as the planter **10** itself) are possible.

FIG. 8 illustrates an embodiment of a setup screen **1200** displayed by the planter monitor **1000** for entering GPS offsets with respect to the tractor. As illustrated in screen **1200** the offset distances include the distance **1202** from the

GPS unit **100** to the centerline of the rear wheels of tractor, a distance **1206** to the centerline of the tractor, a distance **1210** from the centerline of the rear wheels of the tractor to the pivot of the tractor, and a distance **1214** to the ground. It should be appreciated that although the other distances entered in the setup phase as described herein are used to establish the location of the seed tube exit, the distance **1202** to the centerline of the rear wheels of the tractor is used to model the location of the planter **10** while raised in a transport position behind the tractor.

FIG. **9** illustrates an embodiment of another setup screen **1300** displayed by the planter monitor **1000** for entering locations on the planter **10** with respect to the planter pivot point. In addition to selecting a make and model, the operator may be prompted to select the planter frame type and/or hitch style, such as drawn, 2-point pivot, and 3-point. The planter monitor **1000** preferably displays an image **1306** representing the geometry of the selected planter frame type and/or hitch style and prompts the operator to enter distances needed to model the planter geometry. In the illustrative example of FIG. **9**, the planter monitor **1000** requires the operator to enter the distance **1308** between the pivot and the centerline of the gauge wheels **48** as well as the distance **1312** between the pivot and the seed exit. Other frame types and hitch styles will require the operator to measure and input additional or different distances. The planter monitor **1000** assumes transverse distances from the seed exits of each of the row units to the centerline of the tractor based on the planter make and model previously entered by the operator. Alternatively, the operator selects the custom table setup window **1316** and enters transverse distances **1318** from each seed exit to the centerline of the planter **10**.

As part of the initial setup, the operator is preferably prompted to perform a verification routine to verify the GPS offsets entered in the previous setup screens **1200** and **1300**. FIG. **10A** illustrates another embodiment of a setup screen **1400** prompting the operator to place flags **1405** next to the gauge wheels **48** of the rightmost and leftmost row units of the planter **10**. When the operator indicates that the planter **10** is in place, the planter monitor **1000** records a first test location of the GPS unit **100**. FIGS. **10B** and **10C** illustrate embodiments of subsequent setup screens **1410** and **1420** prompting the operator to turn the planter **10** around such that the flags **1405** are adjacent to the gauge wheels **48** on the opposite sides of the planter **10**. When the operator indicates that the planter **10** is in place, the planter monitor records a second test location of the GPS unit **100**.

In yet another embodiment of a setup screen **1430** as illustrated in FIG. **10D**, the sum **1432** of the distances **1202**, **1210**, and **1308** previously entered by the operator is calculated. The measured distance **1435** from the GPS unit **100** to the planter gauge wheels is also determined by dividing the distance along the direction of travel between the first test location and the second test location by two. The operator is prompted to re-measure the previously entered GPS offsets if the measured distance **1435** is different from the sum **1432**. Likewise, the distance **1206** previously entered by the operator is displayed. The measured distance **1445** corresponding to the distance **1206** is determined by dividing the transverse distance between the first test location and the second test location by two. The operator is prompted to re-measure the previously entered GPS offsets if the measured distance is different from the distance **1206** previously entered by the operator.

As illustrated in a further setup screen **1502**, the operator configures the planter swath control. The operator enters the number of swath controllers **1500** and the number of row

units controlled by each swath controller. The operator is preferably able to choose a coverage pattern. In the illustrative embodiment of FIG. **11**, the illustrated planter **10** has four swath controllers **1500** each controlling two row units.

The operator selects windows **1510a**, **1510b**, or **1510c** to choose whether the swath controllers **1500** encounter a stop-planting boundary **1505** at the previously planted seed, at a half-row offset from the previously planted seed, or at full row offset from the previously planted seed, respectively. In the illustrative example of FIG. **11**, the operator has selected a full row offset (**1510c**). The operator selects windows **1520a**, **1520b**, or **1520c** to choose whether the swath controllers are to stop planting when any row of the swath controller crosses the stop-planting boundary **1505** (“Under-Plant”), when any row along transverse line **1515** of the planter crosses the stop-planting boundary **1505** (“50%-50%”), or when every row controlled by the swath controller has crossed the stop-planting boundary **1505** (“Over-Plant”), respectively. In the illustrative example of FIG. **11**, the operator has selected 50%-50% (**1520b**).

In a further setup phase, the operator configures the variable rate drives **1600**. The operator indicates which rows are driven by each variable rate drive **1600**. The operator enters the number of encoder pulses per rotation (discussed later) and the encoder pulse signal frequency (discussed later) of each variable rate drive **1600**. Alternatively, the operator selects a make or type of variable rate drive **1600** which is associated with the same pulse and frequency characteristics.

Continuing the setup phase, the operator is further prompted to enter the number of seeds per disk on the seed meters **30** driven by each variable rate drive **1600**. The operator further initiates a calibration routine (discussed later) in which the seeding control system **1005** drives the seed meters **30** and determines a drive ratio between the variable rate drives **1600** and the seed meters **30**. Alternatively, the operator enters a drive ratio. In addition, the operator prescribes a default seed population rate to be used by the variable rate drive **1600** if the seeding control system **1005** loses the signal from the GPS unit **100**.

The operator further configures the radar system **1205** in a test run. The operator drives the tractor and the planter monitor **1000** receives radar pulses from the radar system **1205**. The planter monitor **1000** determines how far the tractor has traveled using the signal from the GPS unit **100**. The planter monitor **1000** then determines how many radar pulses are received per unit distance traveled. The operator further selects whether the GPS unit **100** or the radar system **1205** is the primary or most trusted speed source used by the planter monitor **1000**. As described later under “Operation,” the planter monitor **1000** will determine whether to override the operator’s choice of primary speed source based on the planter acceleration.

Turning to FIG. **19A**, in a further setup phase the seeding control system **1005** is preferably configured to run a process **1610** to identify an operational problem with the variable rate drives **1600** or swath controllers **1500**. When the process is initiated by the operator at block **1611**, the control unit **350** preferably starts one or more variable rate drives **1600** and engages one or more swath controllers **1500** to drive the seed meters. After a predetermined time period (e.g., 5 seconds) has passed at block **1612**, the control unit **350** stores the subset of rows **12** at which seed pulses are not observed. Preferably, the control unit **350** then disengages one or more swath controllers **1500** at block **1613** and stores the subset of rows **12** at which the seed pulses are observed after a predetermined time at block **1614**. At block **1615**, the

control unit 350 compares expected to actual presence of seeds for each tested configuration and assigns an operational descriptor (e.g., “Good” or “Failed”) to each swath controller 1500 and variable rate drive 1600. At block 1616, the planter monitor 1000 preferably displays an operational summary indicating whether components (e.g., swath controllers 1500 or variable rate drives 1600) are working properly. Turning to FIG. 19B, the operational summary may comprise a screen 1620 including a result summary 1622 of expected and actual observation of seed pulses for each component tested, and preferably includes an alarm indicator 1624 alerting the operator that a component associated with the indicator has failed.

In other embodiments, the control unit 350 may be configured to engage or disengage each variable rate drive and swath controller in series (e.g., from right to left) during a setup phase, allowing the operator to determine by sight or sound whether each component is operating properly.

Calibration

The seeding control system 1005 is preferably configured to use the seed pulses generated by the seed sensors 200 to calibrate the swath controllers 1500 and variable rate drives 1600. The calibration routines described herein measure a delay between a control signal and an operational change detected by the seed sensors 200. The operational change may include changing the rate of seed delivery, stopping seed delivery or starting seed delivery. It should be appreciated, however, that a delay associated with any operational change involving seed delivery could be measured according to the calibration routines described herein.

Calibrating Stop Delay of a Variable Rate Drive

FIG. 12 illustrates an embodiment of a process 2000 to calibrate the variable rate drives 1600. At block 2100, the control unit 350 instructs the variable rate drive 1600 to run. At block 2200, if the control unit 350 does not receive a seed pulse within any predefined time interval, then at block 2250, the planter monitor 1000 prompts the operator to check the seed hopper for seeds 11 or otherwise correct the operation of the planter 10 such that seeds 11 will begin being discharged by the seed meter 30 through the seed tube 32. If the control unit 350 receives a seed pulse, then at block 2300, after a predefined time, the control unit 350 instructs the variable rate drive 1600 to stop driving the seed meter 30 at a time t_0 . Time t_0 is stored by the control unit 350. The control unit 350 then receives seed pulses at block 2400 until no seed pulse is received for a predetermined time (e.g., 5 seconds). At block 2450, the control unit then records the time of the last seed pulse (t_{stop}). The difference between t_{stop} and t_0 represents a stop delay associated with the variable rate drive 1600, which stop delay is calculated and stored by the control unit 350 at block 2455.

Calibrating Start Delay of a Variable Rate Drive

FIG. 13A illustrates an embodiment of a process 2500 to calibrate the variable rate drives 1600. At block 2510, the control unit 350 instructs the variable rate drive 1600 to stop. At block 2520, after a predetermined time, the control unit 350 instructs the variable rate drive 1600 to start driving the seed meter 30 at a time t_0 . Time t_0 is stored by the control unit 350. If a seed pulse is received by the control unit 350 at block 2530, then the control unit records the time of the first seed pulse (t_{start}) at block 2540. The difference between

t_{start} and t_0 represents a start delay associated with the variable rate drive 1600, which start delay is calculated and stored by the control unit 350 at block 2545.

With the start delay and stop delay calibrated, the control unit 350 preferably uses the start delay and stop delay to adjust the time at which the control unit 350 sends control signals to the variable rate drives 1600 such that seed begins to dispense or stops dispensing at the desired position in the field.

According to a preferred process 2550 illustrated in FIG. 13B, the control unit 350 estimates the time to the next stop-planting boundary at block 2552 (preferably using the current planter speed and the distance to the boundary) and compares said time to the motor stop delay at block 2554. If the time to the next stop-planting boundary is equal to the motor stop delay, then the control unit 350 preferably stops the motor at block 2556.

According to a preferred process 2560 illustrated in FIG. 13C, the control unit 350 estimates the time to the next start-planting boundary at block 2562 (preferably using the current planter speed and the distance to the boundary) and compares said time to the motor stop delay at block 2564. If the time to the next start-planting boundary is equal to the motor stop delay, then the control unit 350 preferably starts the motor at block 2566.

Thus the control unit 350 times the subsequent control signals based on the various delays measured as described herein. The above calibration process may be performed during in-field operation in order to determine the start delay and stop delay of the variable rate drives under current or near-current operating conditions.

Calibrating Drive Ratio Between Seed Meter and Variable Rate Drive

FIG. 14 illustrates an embodiment of process 3000 to determine a drive ratio between the variable rate drive 1600 and the seed meter 30. At block 3100, the control unit 350 instructs the variable rate drive 1600 to drive the seed meter 30. At block 3200, if the control unit 350 does not receive a seed pulse, at block 3250, the planter monitor 1000 prompts the operator to check the seed hopper for seeds 11 or otherwise correct the operation of the planter 10 such that seeds 11 will begin being discharged by the seed meter 30 through the seed tube 32. Once the control unit receives a seed pulse at block 3200, the control unit 350 stores the time of the first observed seed pulse (t_1) at block 3300. Once the control unit 350 receives a predetermined number of seed pulses, e.g., 30, at block 3400, the control unit 350 stores the time of the thirtieth seed pulse (t_{30}) at block 3450. The difference between t_{30} and t_1 divided by the number of seed pulses is equal to a time associated with a time between the release of seeds 11 by the seed meter 30 ($t_{nominal}$). The speed w_m of seed meter 30 is then determined according to the following equation:

$$w_m = \frac{1}{(\text{Number of seeds per meter}) \times t_{nominal}}$$

Where: Number of seeds per meter=Total number of seed cavities, apertures or other seed entraining features on each seed meter 30.

The drive ratio R between the variable rate drive 1600 and the seed meter 30 is equal to the ratio between the number of encoder pulses that must be observed before the seed

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meter 30 has made one full revolution and the number of encoder pulses per revolution of the variable rate drive 1600. The drive ratio R is preferably used by the control unit 350 to determine the rate at which to drive the variable rate drive 1600 in order to obtain a given speed w_m of the seed meter and thus a corresponding time $t_{nominal}$ between the release of seeds 11. The values of $t_{nominal}$, w_m , and R are preferably calculated at step 3455 of process flow 3000.

Calibrating Start Delay and Stop Delay of a Swath Controller

FIG. 15A illustrates an embodiment of a process 3500 to determine a clutch start delay and clutch stop delay associated with a swath controller 1500. At block 3510, the control unit 350 instructs the variable rate drive 1600 to run. At block 3525, if the control unit 350 does not receive a seed pulse within a predetermined time at block 3520 (e.g., 5 seconds), then the planter monitor 1000 prompts the operator to check the seed hopper for seeds 11 or otherwise correct the operation of the planter 10 such that seeds 11 will begin being discharged by the seed meter 30 through the seed tube 32. At block 3530, if the control unit 350 receives a seed pulse, then after a predetermined time the control unit 350 instructs the swath controller 1500 to disengage at a time to in order to stop the seed meter 30 from being driven by the variable rate drive 1600. Time to is stored by the control unit 350. The control unit 350 then receives seed pulses at block 3540 until no seed pulse is received for a predetermined time. At block 3550, the control unit then records the time of the last seed pulse (t_{stop}). The difference between t_{stop} and t_0 represents a clutch stop delay associated with the swath controller 1500. The control unit 350 preferably calculates the clutch stop delay at block 3555. After a predetermined time, at block 3560, the control unit 350 then instructs the swath controller 1500 to engage at a time t_0 such that the seed meter 30 is again driven by the variable rate drive 1600. Time t_0 is stored by the control unit 350. At block 3580, if a seed pulse is received by the control unit 350 at block 3570, then the control unit records the time of the first seed pulse (t_{start}). The difference between t_{start} and t_1 represents a clutch start delay associated with the swath controller 1500. The control unit 350 preferably calculates the clutch start delay at block 3585.

The control unit 350 preferably uses the clutch start delay and clutch stop delay to adjust the time at which the control unit 350 sends control signals to the swath controller 1500 such that seed begins to dispense or stops dispensing at the desired position in the field.

According to a preferred process 3600 illustrated in FIG. 15B, the control unit 350 estimates the time to the next stop-planting boundary at block 3652 (preferably using the current planter speed and the distance to the boundary) and compares said time to the clutch stop delay at block 3654. If the time to the next stop-planting boundary is equal to the clutch stop delay, then the control unit 350 preferably disengages the clutch at block 3656. According to a preferred process 3700 illustrated in FIG. 15C, the control unit 350 estimates the time to the next start-planting boundary at block 3762 (preferably using the current planter speed and the distance to the boundary) and compares said time to the motor stop delay at block 3764. If the time to the next start-planting boundary is equal to the motor stop delay, then the control unit 350 preferably starts the motor at block 3766. The foregoing process 3500 may be performed during

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in-field operation in order to determine the clutch start delay and clutch stop delay under current or near-current operating conditions.

Empirical data has shown that even under nearly equivalent operating conditions, there is a variation in clutch stop delay. FIG. 16A shows a graph 4000 illustrating components of delay associated with swath controllers 1500. The x-axis 4145 of graph 4000 represents the distance (in inches) traveled by the planter 10 after the clutch of the swath controller 1500 is disengaged. Data sets 4150 and 4155 represent tests performed at varying seed population rates 4140 in units of seeds per acre. Bars 4100 represent a physical delay (measured in inches traveled) associated with the electronic and pneumatic components of the variable rate drive 1600. Bars 4110 represent a rotational delay (measured in inches traveled) resulting from the mechanical action of the clutch in the swath controller 1500. Bars 4120 represent a delay (measured in inches traveled) associated with the time required for the last seed 11 to be released from the seed meter 30 and pass the seed sensor 200. Each set 4160 of data shows (from bottom to top) the total delay including the rotational delay 4110, the total delay not including the rotational delay 4110, and a last plant range 4130 representing the range between total delay without rotational delay 4110 and with rotational delay 4110.

Continuing to refer to FIG. 16A, the rotational delay 4110 varies because once the clutch is disengaged at a random rotational position of a shaft rotating within the clutch, the clutch will have to rotate through varying degrees before contacting a stopping member. The range in rotational delay 4110 will change based on the seed population rate because the clutch will be rotating faster at higher seed population rates.

Thus a preferred embodiment of seeding control system 1005 is configured to determine a range of delays between a control signal sent to the swath controller 1500 and an operational change in the swath controller 1500, namely engaging or disengaging the clutch. The control unit 350 preferably performs this process multiple times to obtain a distribution of clutch stop delays. The tenth percentile of the distribution of clutch stop delays is approximately equal to the physical delay 4100.

In a preferred process 4500 illustrated in FIG. 16B, the control unit 350 determines and stores a total clutch stop delay (preferably as determined in blocks 3530 through 3555 in process 3500 of FIG. 6) at block 4510. This process is repeated (preferably at the same seed population rate) until clutch stop delay has been determined a threshold number of times (e.g., five) at block 4520. At block 4530, the control unit 350 preferably determines the fixed physical clutch stop delay 4100 (e.g., by finding the tenth percentile of the distribution of total delays). At block 4540, the control unit 350 preferably determines the population-dependent rotational clutch stop delay 4110 (e.g., by subtracting the 10th percentile of the distribution of total delays from the ninetieth percentile of the distribution of total delays).

In operation, when the control unit 350 is accessing the clutch stop delay (e.g., at step 3654 of process 3600 illustrated in FIG. 15B), the control unit preferably modifies the rotational delay 4110 based on the ratio between the population rate at which the rotational delay 4110 was determined and the active population rate. For example, if the rotational delay 4110 was determined at a population of 40,000 seeds per acre, then the rotational delay would be doubled at a population of 20,000 seeds per acre. Thus, the control unit 350 preferably adjusts a predicted component of clutch stop delay based on the active population rate.

As is illustrated in data set **4150** and data set **4155** of FIG. **16A**, by adjusting the time at which the control signal is sent to swath controller **1500** according to this method at each seed population rate **4140**, the last plant ranges **4130** become centered at a desired distance **4160** at each seed population rate **4140**.

In addition, the planter monitor **1000** preferably displays the physical delay **4100**, the rotational delay **4110** and the fall delay **4120** to the operator. The planter monitor also displays the sum of the fall delay **4120** and the physical delay **4100** to the operator. The planter monitor **1000** preferably displays said sum as a “Fixed Delay” and said rotational delay **4110** as a “Variable Delay.” The planter monitor **1000** thus isolates a fixed portion of the clutch delay from a variable portion of the clutch delay associated with the swath control systems **1500**. With this information, the operator is able to see the benefit of making changes in clutch mounting location in order to reduce the variable delay.

It should be appreciated that each calibration routine described herein could be performed prior to planting or in-field during planting. Prior to planting, a calibration routine may be initiated by the operator using a series of screens on the planter monitor **1000**. The cab module **1105** preferably includes switches configured to allow the operator to briefly run the variable rate drives **1600** in order to load the seed meters **30** with seeds **11** prior to a pre-planting calibration routine. These switches may also be used to turn the variable rate drives **1600** on and off during a pre-planting calibration routine. The switches may also be used to selectively engage and disengage the swath controllers **1500** during a pre-planting calibration routine. During planting, as the variable rate drives **1600** and swath controllers **1500** are actually used in the field, the seed sensors **200** preferably continue to provide seed pulses to the control unit **350**. Thus the control unit **350** is preferably able to measure delays associated with the variable rate drives **1600** and the swath controllers **1500** during planting.

Operation

As previously discussed, referring to FIG. **7**, the seed pulses from the seed sensors **200** in each row unit **12** of the planter **10** are communicated to the planter monitor **1000**. The planter monitor **1000** is in electrical communication with the GPS unit **100**, the cab module **1105**, the radar system **1205** and the control unit **350**. The control unit **350** is in electrical communication with the individual swath controllers **1500** and variable rate drives **1600** and the height sensor **705**.

The planter monitor **1000** is preferably configured to allow an operator to enter commands and input data including seed population rates and mapping information. The operator enters a desired seed population rate to the planter monitor **1000**. The operator then pulls the planter **10** across the field. The planter monitor **1000** relays the desired seed population to the control unit **350** and determines the speed of the planter **10** using signals from the GPS unit **100** and/or the radar system **1205**. The planter monitor **1000** displays the speed to the operator and transmits the speed to the control unit **350**. The control unit **350** determines an appropriate speed of the seed meter **30** to obtain the desired seed population rate based on the speed of the planter **10** and other criteria including the size of seed meter **30**, the number of seed-entraining features on seed meter **30**, and other criteria affecting the rate of seed delivery. The control unit **350** determines the actual current speed of the seed meter **30**

based on the encoder pulse of the variable rate drive **1600** and sends an appropriate control signal to the variable rate drives **1600**. Each variable rate drive **1600** is configured to individually variably drive a seed meter **30** in each row unit of the planter **10** at a speed based on the control signal received from the control unit **350**.

The control unit **350** uses a signal from the height sensor **705** to determine whether the planter **10** is lifted in a transport position. If the control unit **350** determines that the planter **10** is in a transport position, it will preferably direct the variable rate drives **1600** to stop driving the seed meters **30**.

The seeding control system **1005** also generates a seed placement map. As each seed **11** passes through the seed tube **32**, the seed sensor **200** sends a seed pulse to the control unit **350**. The planter monitor **1000** associates the time of the seed pulse with a location of the GPS unit **100** and determines the location in the field that the seed **11** was dispensed based on the GPS offsets entered by the operator in the setup phase as previously described. The planter monitor **1000** then adds the position of the seed **11** to a seed placement map that preferably displayed to the operator and is used to determine “stop planting” conditions.

The planter monitor **1000** determines if a stop-planting condition exists for any swath (comprising a single row unit or a set of row units) of the planter **10**, the planter monitor **1000** sends a stop-planting signal to the control unit **350**. The control unit **350** then sends a signal to actuate the swath controller **1500** such that the clutch is disengaged so that the seed meters **30** in the swath are not being driven until the clutch is re-engaged when the stop planting condition passes. The clutches may be any pneumatic or electrical clutches as are known in the art.

The seeding control system **1005** may also be used to alert the operator of operational problems within the variable rate drives **1600** and the swath controllers **1500** using seed pulses during in-field operations. Referring to FIG. **19C**, a preferred process **1630** for providing such alerts to the operator in-field is illustrated. At block **1631**, the control unit determines whether the variable rate drive **1600** associated with the row unit **12** is on. Once the variable rate drive is on, the control unit determines at block **1632** whether the swath controller **1500** associated with the row unit is engaged. If the associated swath controller is not engaged, then at block **1634** the control unit determines whether seeds are being deposited at the row. If seeds are not being deposited, a successful operation descriptor is stored at block **1635**. If seeds are being deposited, a failed clutch operation descriptor is stored at block **1638** and an alarm is preferably displayed to the user. Returning to block **1632**, if the associated swath controller **1500** is engaged, then at block **1633** the control unit determines whether seeds are being deposited. If seeds are being deposited, then a successful operation descriptor is stored at block **1635**. If seeds are not being deposited, then a failed motor operation descriptor is stored at block **1637** and an alarm is preferably displayed to the user.

Where an alarm is displayed as a result of process **1630**, the seeding control system is also preferably configured to determine whether an electrical or hydraulic error has occurred. It should be appreciated that the seeding control system **1005** could also be used to detect other operational problems with the planter **10** that affect the delivery of seeds.

FIG. **17A** illustrates a preferred process **5000** used by the seeding control system **1005** to determine the speed of planter **10**. At block **5100**, the control unit **350** determines whether acceleration of the planter **10** is greater than an

upper threshold (preferably 1.5 ft/s^2) based on the signal provided by horizontal accelerometer **400** at block **5100**. If the acceleration is greater than the upper threshold, the control unit **350** determines the speed of planter **10** using the highest stable value reported by the GPS unit **100** (the “GPS-reported speed”) and the radar system **1205** (the “radar-reported speed”) at block **5150**. The planter monitor **1000** determines whether the GPS-reported speed is stable using an algorithm or other method as is known in the art. The cab module also includes processing circuitry configured to determine whether the radar-reported speed is stable using an algorithm or other method as is known in the art. At block **5200**, if the acceleration is less than the upper threshold acceleration, then the control unit **350** determines whether the acceleration of planter **10** is less than a lower threshold (preferably -1.5 ft/s^2) based on the signal provided by horizontal accelerometer **400**. At block **5250**, if the acceleration is less than the lower threshold rate, the control unit **350** determines the speed of planter **10** using the lowest stable value reported by the GPS unit **100** (the “GPS-reported speed”) and the radar system **1205** (the “radar-reported speed”). At block **5300**, if the acceleration is greater than the lower threshold rate, the control unit **350** determines the speed of planter **10** using the speed input previously selected by the operator. As discussed herein under “Setup,” the planter monitor **1000** is configured to allow a user to select a preferred speed input.

The control unit **350** will often need to stop the variable rate drives **1600** when the planter **10** is not moving. Likewise, the control unit **350** will need to start the variable rate drives **1600** when the planter **10** resumes moving. As previously discussed, empirical data has shown that data from the GPS unit **100** is delayed and untrustworthy at speeds lower than approximately one mile per hour. Empirical data has also shown that the GPS unit **100** will indicate speeds of 0.1 or 0.2 miles per hour when the planter **10** is actually stopped. For these reasons, speed inputs provided by those systems are non-ideal for determining when the planter **10** will stop or determining when the planter **10** has resumed travel. Thus in a preferred embodiment, the control unit **350** predicts a stopping time of the planter **10** using the signal from horizontal accelerometer **400** and sends an appropriately-timed control signal to stop the variable rate drive **1600**.

A preferred process **5500** for carrying out this method is illustrated in FIG. **17B**. When the planter **10** decelerates to a speed less than a threshold speed (preferably 4.5 ft/s) at block **5510**, the control unit **350** determines an estimated stopping time based on the currently utilized speed input and deceleration rates indicated by the horizontal accelerometer **400** at block **5520**. When the stopping time is approximately equal to the stop delay associated with the variable rate drive (preferably determined as described above) at block **5530**, the control unit **350** preferably instructs the variable rate drives **1600** to stop driving the seed meters **30** at block **5540**.

Continuing to refer to FIG. **17B**, after the planter **10** has stopped, the control unit **350** preferably determines that the planter **10** has resumed travel by integrating the signal provided by the horizontal accelerometer **400** at block **1550**. When the speed determined from this method reaches a threshold value at block **5560**, the control unit **350** preferably instructs the variable rate drives **1600** to resume driving the seed meters **30** at block **5570**.

It should be appreciated that the methods described herein may be used to automatically alternate between other speed inputs as are known in the art. Thus the method described herein may be applied whenever one speed input is preferred

over another in a certain range of any kinematic criteria including acceleration or velocity of the planter **10**.

The planter monitor **1000** determines that a stop-planting condition exists when a section of the planter **10** is passing over a previously planted seed based on the seed placement map described above. The planter monitor **1000** also determines that a stop-planting condition exists when a section of the planter **10** travels across a boundary **1505** set by the operator. The boundary **1505** may comprise an outer boundary of the field to be planted or an inner boundary within said field enclosing a waterway or obstacle on which the operator does not wish to dispense seed. The boundary **1505** may also enclose a headland in which the operator intends to plant seed later. The operator may import such boundaries to the planter monitor **1000** using any suitable data storage device, including a USB flash drive, an internet connection, etc. The planter monitor **1000** may also record such boundaries by storing the location of the GPS unit **100** while the operator drives around the boundary. The planter monitor **1000** is preferably configured to allow the operator to instruct the swath controllers **1500** to stop the seed meters **30** during one, all, or any subset of the stop-planting conditions herein described.

FIG. **18** illustrates a user interface screen **6000** displayed on the planter monitor **1000** and configured to allow a user to select stop-planting conditions as described above. The operator may press or select windows **6100**, **6200**, **6300** or **6400** to activate or deactivate a stop-planting condition. When a stop-planting condition is deactivated, the associated window preferably displays the same using a strikethrough or other indicator as illustrated in window **6300**. The operator presses or selects window **6600** to save the set of activated stop-planting conditions. Window **6500** indicates whether swath controllers **1500** are enabled for any stop-planting condition.

It should be appreciated that in addition to the stop-planting conditions described herein, other stop-planting conditions based upon the location, speed, orientation or configuration of the planter **10** could be incorporated into the planter monitor **1000** or designated by the operator.

It should be appreciated that processing functions performed by the control unit **350** as recited herein could also be performed by the planter monitor **1000**. In addition, processing functions performed by the planter monitor **1000** as recited herein could also be performed by the control unit **350**.

The foregoing description is presented to enable one of ordinary skill in the art to make and use the invention and is provided in the context of a patent application and its requirements. Various modifications to the preferred embodiment of the apparatus, and the general principles and features of the system and methods described herein will be readily apparent to those of skill in the art. Thus, the present invention is not to be limited to the embodiments of the apparatus, system and methods described above and illustrated in the drawing figures, but is to be accorded the widest scope consistent with the spirit and scope of the appended claims.

The invention claimed is:

1. A method of calibrating an agricultural planter (**10**) configured to dispense seeds, said method comprising:
 - detecting seeds dispensed by a row unit of the planter with a seed sensor, said seed sensor generating a seed pulse upon the detection of each of said dispensed seeds;
 - sending a start control signal and a stop control signal to a control device, said control device controlling the dispensing of seeds by said row unit;

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determining a start delay by measuring a time delay between the sending of said start control signal and the detection of a first seed pulse after sending said start control signal; and
 determining a stop delay by measuring a time delay 5 between the sending of said stop control signal and the detection of a last seed pulse after sending said stop control signal.
 2. The method of claim 1, wherein said control device is a swath controller, said swath controller controlling a drive 10 that controls dispensing of seeds by said row unit.
 3. The method of claim 1, wherein said control device is a drive that controls dispensing of seeds by said row unit.
 4. The method of claim 2, further comprising:
 repeating multiple times said step of measuring said time 15 delays; and
 determining a portion of said measured time delays which are dependent upon a rate at which seeds are dispensed by said row unit.

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5. The method of claim 1, further comprising:
 storing said measured time delays in memory.
 6. The method of claim 1, further comprising:
 prompting an operator to check a seed supply upon 5 detection that no seeds are being dispensed by said row unit within a predefined time interval after sending a start control signal.
 7. The method of claim 1, wherein said control device controls a seed meter associated with said row unit, and 10 wherein said measured time delay is a time between detection of a first seed dispensed by said seed meter and detection of a selected number of seeds dispensed by said seed meter, and further comprising:
 15 calculating a speed of said seed meter; and
 calculating a drive ratio between said variable rate drive and said seed meter.

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